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⑤④ **Automatic testing of a plurality of smoking articles.**

⑤⑦ A flexible automatic test facility for measuring physical parameters or smoking articles and components of smoking articles, e.g., filter portions is disclosed. The test facility includes a microprocessor based controller device 1000, means 300 for severing the filter portion from the article, a plurality of instruments 200, 600, 700, 800, 850 for performing the desired measurements and a computer-controlled robot 503 for gripping and maneuvering one cigarette at a time to one or more of the instruments or severing means to measure one or more physical characteristics of each article or its components in accordance with software instructions. A hopper feeder 100 device containing a plurality of sample sets in separate bins in an indexing mechanism may be provided for extended unattended operation. Each sample set is provided with a code and a database including the nominal physical characteristics of the samples in the set and the test sequence for the cigarettes in the sample set. The test sequence and parameters for each article in each set are obtained from the database, and the controller instructs the robot to grip a fed cigarette and to advance that cigarette to one or more of the instruments for performing measurements processing station for severing filter in accordance with the predetermined sequence of measurements. At the conclusion of the samples in a given sample set, the next sample set is loaded, identified, and the process continues in accordance with the predetermined sequence for that sample set.

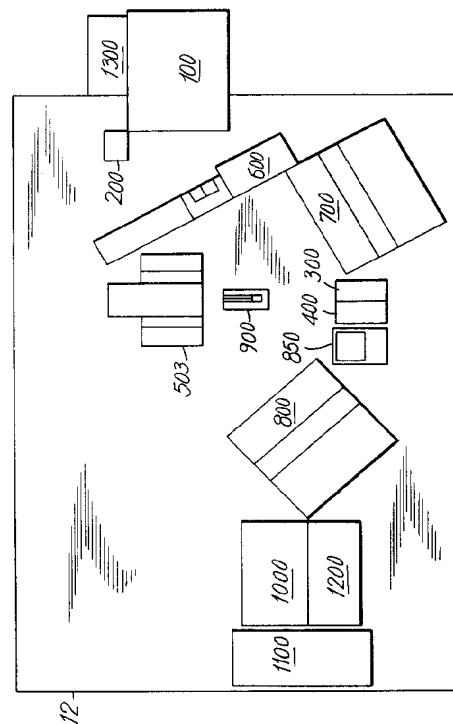


FIG. 1

Background of the Invention

This invention relates to an automatic test station for handling bundles of smoking articles and performing one or more of a plurality of physical measurements on individual smoking articles and components thereof. More particularly, this invention relates to an automatic test station having a plurality of measuring stations and a robotic device for maneuvering differently dimensioned smoking articles to one or more of the measuring stations in a preselected sequence in an unattended mode.

It is common practice to perform a sequence of one or more tests or measurements on commercial and experimental smoking articles and their component parts following assembly. These measurements include the physical characteristics of the article and component parts (e.g., the filter) such as article pressure drop, ventilation, filter pressure drop, article circumference, article length, filter length, filter and tobacco weights, and paper permeability. A plurality of like smoking articles are subjected to tests that measure one or more of those specific properties. The test results may be used to evaluate the uniformity of the measured property or properties from article to article within the plurality of like articles and to obtain statistical data regarding the characteristics of the like articles in that plurality of articles. In addition, multiple pluralities of like articles, wherein the articles in each plurality may be different, are typically subjected to the same series of tests under conditions that permit comparing the statistical characteristics of the different like articles.

Tests may be performed both on the complete article and separately on components of a complete article. For example, the filter portion of a filter-tipped smoking article may be measured for pressure drop, circumference and size. This requires that the filter be severed from the smoking article. Any tobacco shreds that remain affixed to the filter are removed from the filter portion.

In conventional testing, a series of conventional test insert ents are arranged in a work area. An operator manually places each smoking article, or its component, into each instrument and actuates the insert ent to conduct the desired measurement. The test result, i.e., the measured parameter is then displayed on the insert ent and the data are typically transmitted to a host computer for recordation in a database. The database is used for subsequent analysis and tabulation. To measure component parts, the operator must manually sever the component from the article, dispose of the remainder of the article (or save it for subsequent testing), and then insert the component into the proper instrument or instruments to acquire the desired measurements. For example, to conduct tests on the filter rod portion of a conventional cigarette, the filter rod is typically severed from the cigarette using a razor blade to cut through the tobacco portion, and any tobacco shreds remaining attached to the filter are removed by the operator using a small instrument or a finger. The cleaned or deshredded filter is then inserted into the measuring insert ents and the data acquired.

One problem with this technique is that it requires an operator to be in attendance throughout the procedure. Tests on manually guided articles also may be subject to variations in how or where the smoking article is gripped and/or positioned during the measurement procedure. These variations are undesirable for obtaining accurate statistical data.

Fidus-Instrument Corporation, Richmond, Virginia, has available a product line under the trade name Automatic Test Stations. The automatic test stations provide combinations of instruments for measuring one or more of weight, circumference/diameter, ventilation, pressure drop, and hardness. Model numbers CTS 500, CTS 400, CTS 350, and CTS 300 are automatic test stations for testing only cigarettes. Model numbers FTS 400 and FTS 300 are automatic test stations for testing only filter rod portions. The different numerical designations indicate that different combinations of instruments for performing various measurements are combined into a single CTS or FTS station. The measuring units are stacked on top of each other so that each article or filter rod to be tested is downwardly and sequentially indexed along an axis through the instruments.

The automatic test stations are available in conjunction with a product under the trade name Automatic Hopper Loader, model number AHL 100, also available from Fidus Instrument Corp. The Automatic Hopper Loader device has a plurality of bins for receiving bundles of a plurality of smoking articles (or filter rods) that may be loaded with up to eighteen bundles of smoking articles (or filter rods) simultaneously. The commercial hopper device transfers the contents of one bin to a hopper area. The contents loaded in the hopper area are then fed, one at a time, into either a CTS or FTS device, to which the hopper is mated. The bins are then indexed to bring the next bin into position for unloading into the hopper. The CTS and FTS automatic test station devices are capable of providing the results of the acquired test data to a master computer for tabulation and recordation.

One problem with these prior commercial devices is that they are not sufficiently flexible to alter the test sequence of individual samples among each bundle or from bundle to bundle. Rather, each model Automatic Test Station is configured with a sufficiently broad number of tests which are performed on each smoking article or filter rod fed into the Station. Thus, unnecessary tests are performed. Also, if one insert ent module in a station becomes inoperative, the entire station becomes inoperative until that module can be repaired or replaced.

Another problem with these prior devices is that they are not capable of performing tests on a selected

smoking article, followed by performing tests on a component of that smoking article, for example, the filter rod portion. Rather, a second Automatic Test Station of the FTS series must be obtained, in addition to a CTS series station, and an operator must manually sever the filter from the smoking articles measured by the CTS station and insert the severed filters into the FTS station for the filter measurements.

It is known to use robotic devices having opposing members for grasping and maneuvering objects from one location to another for assembling structures and for preparation of samples, e.g., dilution or mixing of chemical materials, prior to introduction to an analytical instrument in an analytical laboratory. One such device is the MasterLab™ System available from Perkins-Elmer Corp., Norwalk, CT 06856. However, it is not known to use such devices for gripping and maneuvering a plurality of different smoking articles. One of the problems with such robotic systems is that they are not readily capable of grasping differently dimensioned crushable, nonresilient objects such as smoking articles without damaging at least some, if not all, of such articles. More particularly, such robotic devices typically do not have the ability to grasp securely a preselected range of differently dimensioned smoking articles without deforming at least some articles in the range. The use of force transducers to monitor the forces exerted to control gripping of the article has been considered. However, such transducers increase the cost and complexity of the device. Also, because such transducers monitor force, they do not detect whether the deformable article is securely gripped and not deformed or damaged. Thus, such force transducers are not likely to prevent the opposing members from damaging relatively fragile smoking articles.

Accordingly, there is a continuing need for automatic test stations that are flexible in operation and can be programmed to perform a desired series of tests of measurements. Further, there is a need for such automatic test station that can operate in an unattended mode.

It has, therefore, been desired to provide an automated test station for obtaining one or more measurements on a smoking article selected from among a plurality of possible measurements. It is another object to provide a programmable automated test station for conducting different tests on different smoking articles in an unattended mode. It has also been desired to provide an automated test station that can conduct measurement tests on multiple sets of samples consecutively in an unattended mode.

It has also been desired to provide an automatic test station that can perform a selected sequence of characterization measurements on a smoking article and on a component of that article. It has also been desired to provide a robotic device for gripping and maneuvering each smoking article and smoking article component.

It has also been desired to provide an automated test station that can be instructed to conduct different test protocols on different samples within a sample set and on samples within different sample sets.

It has also been desired to provide an automated test station that can conduct measurement tests using conventional measuring instruments with minimal modification. It has also been desired to provide a test station that can be manually operated when necessary or desirable.

It has also been desired to provide an automated test station that can communicate with a computer device to receive information regarding the tests to be conducted and to transfer data for subsequent evaluation.

Summary of the Invention

In accordance with the present invention, a computer-controlled robotic automatic test station that measures a selected number of a plurality of physical parameters of smoking articles and/or smoking article components in a selected sequence is provided.

One aspect of the present invention is directed to an apparatus for measuring a physical characteristic of a plurality of smoking articles. One such apparatus comprises:

- means for gripping and releasing a smoking article;
- means for maneuvering a gripped smoking article within a range of motion;
- means for receiving one of said plurality of smoking articles at a first location within the range of motion;
- means for measuring a physical characteristic of a smoking article, the measuring means being at a second location within the range of motion; and
- means for controlling the gripping and releasing means and the maneuvering means to grip the one smoking article at the first location and to maneuver the one smoking article to the measuring means so that the physical characteristic of the one smoking article can be measured.

In one embodiment, the controlling means is a microprocessor which controls the gripping and releasing means to release the one smoking article at the measuring means so that the physical characteristic can be measured and to grip the one smoking article at the measuring means following the measurement. Preferably, the gripping and releasing means and the maneuvering means are a robot having a first member and a second member, the first and second members being movable in opposition for gripping therebetween a smoking article.

In a preferred embodiment of such an apparatus, the measuring means further comprises a first means for measuring a first physical characteristic of a smoking article located at the second location and a second means for measuring a second physical characteristic of a smoking article, the second measuring means being located at a third location within the range of motion, and wherein the controlling means controls the gripping and releasing means and the maneuvering means to grip the one smoking article at the first location and to maneuver the one smoking article to one of the first and second measuring means whereby one of the first and second physical characteristics can be measured. The controlling means preferably also controls the gripping and releasing means and the maneuvering means to maneuver the one smoking article from the one of the first and second measuring stations to the other of the first and second measuring means whereby the other of the first and second physical characteristics can be measured.

In an alternate preferred embodiment of such an apparatus, the measuring means further comprises more than one means for measuring more than one selected physical characteristics of a smoking article wherein each said means is located at a different location within the range of motion and measures a different physical characteristic, said means being selected from among the group consisting of means for measuring circumference, means for measuring pressure drop and means for measuring length, and for filter-tipped smoking articles, means for measuring ventilation, and wherein the controlling means controls the gripping and releasing means and the maneuvering means to maneuver the one smoking article to one or more of the measuring means. The controlling means preferably further comprises a means for providing a test sequence identifying one or more physical characteristics of the one smoking article to be measured, wherein the controlling means is responsive to the test sequence and controls the gripping and releasing means and the maneuvering means to maneuver the gripped one smoking article to one or more of the measuring means so that the one or more identified physical characteristics can be measured. In a preferred embodiment, the test sequence identifies the order in which the measurements of the one smoking article are to be made, and more preferably the order in which the measurements of each smoking article in the plurality of smoking articles are to be made.

Another aspect of the present invention is directed toward an apparatus for measuring a physical characteristic of a component of a plurality of smoking articles. One such apparatus includes:

- means for gripping and releasing a smoking article;
- means for maneuvering a gripped smoking article within a range of motion;
- means for receiving one of said plurality of smoking articles at a first location within the range of motion;
- means for severing the component of the smoking article from the smoking article, the severing means being located at a second location within the range of motion;
- means for measuring a physical characteristic of a smoking article component, the measuring means being at a third location within the range of motion; and
- means for controlling the gripping and releasing means and the maneuvering means to grip the one smoking article at the first location and maneuver the one smoking article to the severing means, and to maneuver the one smoking article component to the measuring means so that the physical characteristic of the one smoking article component can be measured.

In one embodiment, the controlling means is a microprocessor which controls the gripping and releasing means to grip the one smoking article by its component, release the one smoking article component at the measuring means so that the physical characteristic of the one smoking article component can be measured, and grip the one smoking article component at the first measuring means following the measurement. Preferably, the gripping and releasing means and the maneuvering means are a robot having a first member and a second member, the first and second members being movable in opposition for gripping therebetween a smoking article.

In a preferred embodiment of such an apparatus, the measuring means comprises a first measuring means for measuring a first physical characteristic of a smoking article component located at the third location and a second means for measuring a second physical characteristic of a smoking article component, the second measuring means being located at a fourth location within the range of motion, and wherein the controlling means controls the gripping and releasing means and the maneuvering means to grip and maneuver the one smoking article component to one of the first and second measuring means whereby one of the first and second physical characteristics can be measured. The controlling means preferably controls the gripping and releasing means and the maneuvering means to maneuver the one smoking article component from the one of the first and second measuring stations to the other of the first and second measuring means whereby the other of the first and second physical characteristics of the smoking article component can be measured. The first and second measuring means are preferably selected from among the group consisting of means for measuring ventilation, means for measuring pressure drop, and means for measuring length.

In an alternate preferred embodiment of such an apparatus, the measuring means further comprises a first means for measuring a first physical characteristic of a smoking article component and a second means for

measuring a second physical characteristic of a smoking article, the second measuring means being at a fourth location within the range of motion, wherein the controlling means controls the gripping and releasing means and the maneuvering means to grip the one smoking article at the first location, to maneuver the one smoking article to the second measuring means so that the first physical characteristic of the one smoking article can be measured, and then to the severing means, thereby to sever the component, and to maneuver the one smoking article component to the first measuring means so that the first physical characteristic of the one smoking article component can be measured.

Alternately, the first measuring means further comprises more than one means for measuring more than one physical characteristic of a smoking article component at more than one location in the range of motion, the second measuring means further comprises more than one means for measuring more than one physical characteristic of a smoking article located at more than one location in the range of motion, and the controlling means further comprises a means for providing a test sequence identifying one or more physical characteristics of the one smoking article and one or more physical characteristics of the one smoking article component to be measured, wherein the controlling means is responsive to the provided test sequence and controls the gripping and releasing means and the maneuvering means to maneuver the gripped one smoking article to one or more of the second measuring means, and the severing means, and one or more of the first measuring means so that the one or more identified physical characteristics of the smoking article and the smoking article component can be measured. The test sequence may identify the order in which the measurements of the one smoking article component are to be made and more preferably the order in which the measurements of each smoking article component of the plurality of smoking article are to be made. The physical characteristics of a smoking article are obtained prior to the physical characteristics of a smoking article component.

In one embodiment, the apparatus includes a second means for receiving a smoking article at a fifth location within the range of motion wherein the microprocessor means controls the gripping and releasing means and the maneuvering means to release the one smoking article onto the second receiving means and then to grip the smoking article by its component on the second receiving means, to maneuver the one smoking article to the severing means, and to grip the one smoking article component during the severing process. Preferably, each smoking article component is a filter rod of a cigarette and the apparatus further comprises a means for deshredding the severed filter component of a cigarette, wherein the microprocessor means controls the gripping and releasing means and the maneuvering means to maneuver a severed filter to the deshredding means following the severing operation.

Another aspect of the present invention is directed toward a method for measuring a physical characteristic of a plurality of smoking articles at a test station having a means for gripping and releasing a smoking article, means for maneuvering a gripped smoking article within a range of motion, means for receiving one of said plurality of smoking articles at a first location within the range of motion, means for measuring a physical characteristic of a smoking article, the measuring means being at a second location within the range of motion; and microprocessor means for controlling the gripping and releasing means and the maneuvering means. One such method comprises the steps of providing a plurality of smoking articles;

feeding one fed smoking article to the receiving means;

gripping the one smoking article at the receiving means;

maneuvering the gripped one smoking article to the measuring means; and

measuring the physical characteristic of the one smoking article.

In an alternate embodiment the method includes releasing the one smoking article at the measuring means so that the physical characteristic can be measured and gripping the one smoking article at the first measuring means following the measurement.

Preferably, the gripping and releasing means and the maneuvering means are a robot having a first member and a second member movable in opposition, and gripping and releasing the one smoking article further comprises moving the first and second members together for gripping a smoking article and moving the first and second members apart to release the smoking article.

In yet another embodiment, wherein the test station includes more than one means for measuring more than one selected physical characteristics of a smoking article and each said means is located at a different location within the range of motion, said means being selected from among the group consisting of means for measuring circumference, means for measuring pressure drop and means for measuring length, the method further comprises the steps of:

providing a test sequence identifying one or more physical characteristics of the one smoking article to be measured;

gripping and maneuvering the one smoking article to one or more of the measuring means in response to the provided test sequence so that the one or more identified physical characteristics can be measured. Preferably, providing the test sequence further comprises identifying the order in which the measurements of the

one smoking article are to be made, and more preferably, identifying the order in which the measurements of each smoking article in the plurality of smoking articles are to be made.

Another aspect of the present invention is directed towards a method for measuring a physical characteristic of a component of a plurality of smoking articles in a test station having means for gripping and releasing a smoking article, means for maneuvering a gripped smoking article within a range of motion, means for receiving one of said plurality of smoking articles at a first location within the range of motion, means for severing the component of a smoking article from the smoking article, the severing means being located at a second location within the range of motion, means for measuring a physical characteristic of a smoking article component, the measuring means being at a third location within the range of motion, and microprocessor means for controlling the gripping and releasing means and the maneuvering means. One such method comprises:

- providing a plurality of smoking articles;
- feeding one smoking article to the receiving means;
- gripping the one fed smoking article by its component;
- maneuvering the gripped smoking article to the severing means;
- severing the one smoking article component from the one smoking article;
- maneuvering the one smoking article component to the measuring means; and
- measuring the physical characteristic of the one smoking article component.

Optionally, the method further comprises releasing the smoking article component at the measuring means so that the physical characteristic of the one smoking article component can be measured and gripping the one smoking article component at the measuring means following the measurement.

Preferably, the gripping and releasing means and the maneuvering means are a robot having a first member and a second members movable in opposition and the step of gripping the one smoking article or one smoking article component further comprises moving the first and second members together and the step of releasing the one smoking article component further comprises moving the first and second members apart.

In one preferred embodiment, the measuring means further comprises one or more means for measuring one or more physical characteristics of a smoking article component selected from among the group consisting of means for measuring ventilation, means for measuring pressure drop and means for measuring length, and one or more means for measuring one or more physical characteristics of a smoking article, each measuring means being located at a different location within the range of motion, wherein the method further comprises:

- providing a test sequence identifying one or more of the physical characteristics of the one smoking article and the one smoking article component to be measured;
- gripping and releasing and maneuvering the one smoking article to one or more of the measuring means and the severing station in response to the identified sequence so that the one or more of the identified physical characteristics of the one smoking article and the one smoking article component can be measured.

Preferably, providing the test sequence further comprises identifying the order in which the measurements of the one smoking article and the one smoking article component are to be made, and more preferably the order in which the measurements of each smoking article and smoking article component of the plurality of smoking articles are to be made.

In one preferred embodiment, the test station includes a second means for receiving a smoking article at a fourth location within the range of motion and the step of maneuvering the gripped one smoking article to the severing means further comprises:

- maneuvering the gripped article to the second receiving means,
- releasing the one smoking article on the second receiving means;
- gripping the one smoking article component while the article is on the second receiving means; and
- maneuvering the one smoking article to the severing means so that the gripping means grips the one smoking article component during the severing process.

Preferably, the smoking article and its component further comprise a tobacco-containing cigarette and a filter tip and the method further comprises:

- maneuvering the gripped filter severed from the cigarette to a means for deshredding the filter of any tobacco prior to measuring the physical characteristic of the filter, the deshredding means being at a fifth location in the range of motion.

In one aspect, the invention concerns providing a robot, a system microprocessor controller, a selected number of misting laboratory measuring instruments, and a smoking article severing station. The microprocessor device controls the robot, instruments, and severing station so that each article or component to be tested is maneuvered through a predetermined sequence of tests. A hopper feeder device may be provided so that several sets of samples can be loaded at one time into separate bins in that device whereby each sample set is identified with a code and the physical parameters of the samples in each set are enumerated and assigned to that code. In addition, the sequence of the tests to be run on the samples in the set and which tests are to

be run on which samples are established in a database that is associated with the code. Thus, when a bin of samples is to be processed, the code is read and the appropriate database parameters are incorporated into the instructions to the robot so that samples are properly maneuvered into the proper position for conducting the selected measurements to be performed in the selected sequence.

5 In operation, the system controller instructs the hopper-feeder to unload one hopper-bin containing a sample set into a feeder device and to feed one article from that set at a time. The system controller reads the code associated with that bin and sample set and adjusts the instructions to be delivered to the robot to account for the parameters of the samples to be measured and the tests sequence to be conducted. The system controller then instructs the robot to grip an article and place it into the selected test instruments in the selected
10 sequence, to obtain the test results and data, optionally to print the data, and preferably to transmit the acquired data to a host computer for further processing. The system controller counts the number of samples processed and advances the hopper feeder to unload another sample set for the next test sequence.

Advantageously, in the present invention, a flexible automatic test station is provided which can increase overall productivity by allowing the system operator to perform other duties or tests that are not susceptible to robotic controlled performance while the test station is processing multiple sample sets. These duties also could include reviewing test data and loading additional sample sets into the station. Also, a station in accordance with the present invention can be operated in an unattended mode, and thus can conduct tests after regular work hours to accommodate peak work loads without requiring training of additional operators to conduct the tests manually. In addition, because the test station uses conventional instruments, those instruments can be
20 manually used when the automatic feature of the test station is not being used. Another advantage to the flexible test station of the present invention is that it can be modified as needed by the addition or deletion of various measuring instruments (modified for remote microprocessor control). Yet another advantage is that if one instrument becomes inoperative, the test station may stop operation and alert an attending operator or, if unattended, skip the inoperative instrument and continue to perform the other tests on the samples in the sample sets.

25 Brief Description of the Drawings

Further features of the invention, its nature and various advantages will be more apparent from the accompanying drawings and the following detailed description of the invention, in which like reference numerals refer
30 to like elements, and in which:

- FIG. 1 is a schematic top plan view of the present invention;
- FIG. 2 is front view of the hopper feeder and length measuring station of FIG. 1;
- FIG. 3 is a side view taken along line 3-3 of FIG. 1;
- FIG. 4 is a top view taken along line 4-4 of FIG. 2;
- 35 FIG. 5 is a side sectional view taken along line 5-5 of FIG. 2;
- FIG. 6 is a representative view of one embodiment of the field of view of the length measuring station;
- FIG. 7 is a representative view of a second embodiment of the field of view of the length measuring station;
- FIG. 8 is a front sectional view of severing station 300 of FIG. 1;
- FIG. 9 is a side view taken along line 9-9 of FIG. 8;
- 40 FIG. 10 is a partial sectional view of the deshredding station of FIG. 1;
- FIG. 11 is a side view of the deshredder tool of FIG. 1;
- FIG. 12 is an end view taken along line 12-12 of FIG. 11
- FIG. 13 is a front plan view of the gripping mechanism of FIG. 21;
- FIG. 14 is a side view taken along line 14-14 of FIG. 13;
- 45 FIG. 15 is a side view taken along line 15-15 of FIG. 13;
- FIG. 16 is a front view taken along line 16-16 of FIG. 15;
- FIG. 17 is a side view of a grasping member taken along line 17-17 of FIG. 13;
- FIG. 18 is a front view taken along line 18-18 of FIG. 17;
- FIG. 19 is a partial sectional view taken along line 19-19 of FIG. 13;
- 50 FIG. 20 is a front view taken along line 20-20 of FIG. 19;
- FIG. 21 is an elevated perspective view of the robot of FIG. 1;
- FIG. 22 is an side view of the reorientation fixture of FIG. 1;
- FIG. 23 is an end view taken along line 23-23 of FIG. 22; and
- FIG. 24 is top view taken along line 24-24 of FIG. 22.

55 Detailed Description of the Invention

Referring to FIG. 1, station 10 in accordance with a preferred embodiment of the invention includes table

12, robot 503, hopper-feeder 100, station 200 for measuring the length of an article, circumference station 600 for measuring the circumference of the smoking article, PDI station 700 for measuring the smoking article pressure drop and filter ventilation, fixture 900 for reorienting a smoking article, severing station 300 for severing an article component from the article, deshredding station 400 for removing tobacco shreds from the severed component, PDI 800 for measuring the filter pressure drop, station 850 for measuring the length of a filter, and micro-processor 1000 for controlling the operation of station 10. Associated with station 10 is host coomputer 1200 for containing test protocols and paramaters in a database listing and acquiring test data for for tabulation, evaluation and analysis. Additionally, station 10 includes operator workstation 10.

Table 12 is preferably a flat table for supporting the various devices, insert instruments, and processing stations at positions within the reach of robot 503. Table 12 is sufficiently large, e.g., 1.5m by 2m (five feet by seven feet), to restrict an operator from interfering with the motion of robot 503 and either injuring the operator or halting the motion of the robot.

Referring to FIGS. 1-5, hopper feeder 100 has a plurality of pockets 110 attached to a continuous belt 120 that travels around sprockets 122. In one embodiment, belt 120 is indexed to advance the plurality of pockets 110 a distance corresponding to the spacing between each pocket. In the preferred embodiment, each pocket 110 is capable of containing a sample set of a plurality of smoking articles 20, for example, up to thirty articles, preferably of the same type or brand. Each pocket 110 will typically contain a sample set of a plurality of like articles 20 that may be the same or different from each sample sets in other pockets.

An unloading device 130 is positioned at a selected location relative to the path of belt 120 so that as one of pockets 110 is indexed into alignment with device 130, the contents of the one pocket are transferred from that pocket into device 130. Unloading device 130 may be a paddle or flange that pushes the articles out of pocket 110 or alternatively manipulates pocket 110 to release its contents. Referring to FIG. 2, device 130 moves from an extreme left position to an extreme right position in a range of travel. One pocket 110 is indexed into alignment with device 130, which is then moved from its extreme right position to its extreme left position, thereby pushing articles 20 out of the one pocket 110 and into a feed mechanism 140.

Feed mechanism 140 dispenses the articles in device 130 one at a time into chute 220. One such feed mechanism 140 may be, for example, a V shaped feed structure 150 having an aperture 152 at the vertex so that articles 20 are fed through the vertex aperture one at a time, and a device for receiving one article at a time for transferring that article to chute 220 (not shown). Preferably, the plurality of articles 20 in pockets 110 are longitudinally aligned with chute 220 so that no angular manipulation is required.

Hopper feeder 100, unloading device 130, and feed mechanism 140 are preferably a commercial device, for example, model AHL 100, purchased from Fidus Instrument Corporation. The commercial device is constructed with a funnel type feed mechanism for feeding the contents that are unloaded from a pocket one at a time, in a vertical direction downwardly, to an interconnected commercial CTS or FTS test station. For adaptation for use with the present invention, the conventional funnel mechanism was removed and the commercial hopper feeder device was installed at one edge of table 12 proximate to chute 220 so that chute 220 receives at an angle each article 20 as it is fed out the feed mechanism provided with the commercial device. Thus, each article 20 slides down chute 220 at an angle to horizontal.

The commercial device also was modified by the addition of feet (not shown) so that it would stand on the floor. Hopper system 100 as purchased contained motor drive electronics and controls that connected directly to a computer. This required that the computer send a pulse to the stepping motor each time belt 120 was moved, requiring 16,000 pulses to index from one pocket 110 to the next. To offload computer 1000 from this task and so that computer 1000 may be used for other potential tasks, a commercial preset indexer was added (not shown). This device is programmed to generate the required number of pulses when computer 1000 toggles a digital input on the indexer. The indexer is capable of generating the control signals for device 130, thus offloading control computer 1000. The digital input on the present indexer can also be toggled using a pushbotton, allowing manual control of the system 100. This manual control may be used for set-up and adjustments to system 100 and for troubleshooting, all without use of computer 1000. The as purchased control of feed mechanism 140 likewise required computer control to monitor the index detector, to determine when to stop the motor driving device 140. Hopper system 100 was similarly modified to work independently, turning the feed mechanism one revolution and stopping automatically whenever a digital input is toggled to start the motor rotation.

Referring to FIGS. 1 and 13-21, robot 503 includes base 590, rotating platform 591, pivoting member 592, pivoting arm 593, hand 500, and opposing members 510 and 520. Base 590 provides base rotation in the horizontal plane of robot 503 about an axis and is secured to table 12. Pivoting member 592 provides for shoulder joint movement by rotating in a two dimensional vertical plane. Pivoting member 593 provides for elbow joint movement by rotation in a two dimensional vertical plane. Hand 500 provides a wrist pitch motion and wrist rotation motion in three dimensions. Hand 500 includes means for translating a pair of opposing members 510

and 520 for gripping one smoking article 20 toward and away from each other so that the opposing members contact and grip article 20 securely without deforming article 20.

Robot 503 preferably has five independently controlled axes with position repeatability of ± 0.5 mm, and a maximum reach in the range of from about 600mm to 700mm (24 to 27 inches). Robot 503 is controlled by microprocessor 1000 and is thus capable of operating unattended and repeatedly performing each of the possible sequences or processes with the same accuracy and precision. Because it is a software controlled device, robot 503 can be controlled by appropriate programming to perform a sequence of motions which may be the same or different for each article that is gripped and maneuvered as described below.

Robot 503 is preferably a model Movemaster 11, manufactured by Mitsubishi, Inc., of Japan, and available from Perkin-Elmer Corporation as part of a product known as the MasterLab™ System. The MasterLab™ device includes as microprocessor 1000 an IBM PC computer, model AT, having an Intel 8088 microprocessor device, 286 kilobyte memory, and software appropriate to control the initialization and motion of robot 503 relative to base 590 in the five dimensions and, thus, relative to each of the stations with which robot 503 interacts as described herein. The software for controlling the motion of the robot uses the commercial known programming language PERL (Perkin-Elmer Robot Language), which is a menu driven language having a dedicated command structure. Microprocessor 1000 also is provided with appropriate and conventional data communication ports to control the various test instruments to perform the desired measurements when the smoking article or the filter portion or other component is inserted into the measuring station, and to receive test data obtained. Appended hereto as a software appendix is a software listing for operation of robot 503 of automatic test station 10 in accordance with the present invention.

Referring to FIGS. 13-20, a preferred embodiment of the opposing gripping members of robot 503, in accordance with the present invention, are shown. First member 510 is secured to flange 501 and support member 560 (and hence member 520) is secured to corresponding flange 502 so that members 510 and 520 are generally disposed in relatively fixed angular orientations, e.g., in parallel, and have opposing respective inner surfaces 511 and 521. Force altering means 570 is connected to support member 560 and second member 520. It provides for moving member 520 relative to support 560 to alter or adjust the force exerted on gripped smoking article 20, thereby to maintain the force below the force that would otherwise be imposed on smoking article 20 if there was no such movement, and below a selected maximum force that might crush or deform article 20.

In the preferred embodiment, force altering means 570 includes lever 530, spring 540, stop 550, and pin 563. Lever 530 is secured at one end to member 520 by bolt 531. Spring 540 is set within receptacle 541 milled in support 560 and urged against lever 530. Member 520 is pivotally secured to support 560 between yokes 561 and 562 about pin 563. Stop 550 is adjustably secured to support 560 so that it extends a selected distance from support 560. Stop 550 includes a flange 551 that is configured to fit over end 533 of lever 530. Spring 540 thus urges lever 530 against stop 550 flange 551. The range of motion of lever 530, and hence member 520, is limited by the motion of lever end 533 between support 560 and stop 550 as lever 530 pivots about pin 563. The position of stop 550 is adjustable to control the range of motion and is typically set so that member 520 is normally biased parallel to member 510 when not in contact with any article 20. Stop 550 also is used to keep member 520 from over-extending towards member 510 due to the force that spring 540 exerts on lever 530.

In an alternate embodiment, stop 550 could be adjusted so that tip 522 is biased closer to tip 512 than yokes 561 and 562 are spaced to member 510. This provides for gripping a slightly greater range of differently dimensioned articles as compared to when members 510 and 520 are biased parallel, but makes positioning members 510 and 520 about each article more difficult, requiring a comparatively larger distance between members 510 and 520 in the open position. Similarly, member 570 could be adjusted so that some of the force that would otherwise be exerted by members 510 and 520 on article 20 is altered when each article in this preselected range of differently dimensioned articles is gripped.

Member 520 has a notch 525 cut in surface 521 near tip 522 and member 510 has a corresponding notch 515 cut in opposing surface 511 near its tip 512. Notches 515 and 525 are thus in opposition for gripping a smoking article 20 therebetween. Notches 515 and 525 each preferably comprises two planar surfaces that intersect at an angle α of approximately 90 degrees. Further, the notches are arranged to form a receptacle for receiving and supporting article 20.

The shape and dimension of notches 515 and 525 are chosen so that a preselected range of dimensions of differently dimensioned smoking articles 20 can be supported and securely gripped by opposing forces exerted by members 510 and 520. Differently dimensioned articles thus may have different contact points on the respective planar surfaces. Furthermore, notches 515 and 525 are configured so that each smoking article is held rigidly in place along four contact points between members 510 and 520 and does not "slip" axially or longitudinally while it is being maneuvered from station to station or held in place at a station. Other angles and contoured shapes for notches 515 and 525 may be used.

In a preferred embodiment, the gripping surfaces of notches 515 and 525 are lined with conventional emery paper, for example, 240 grade, or some other mildly abrasive material to increase the friction between smoking article 20 and members 510 and 520 and to minimize slip.

In operation, upon an appropriate instruction from microprocessor 1000, flanges 501 and 502 are translated to an "open" position spaced apart a first distance and hand 500 is maneuvered to position notches 515 and 525 on opposite sides of and in alignment with a selected smoking article 20. Article 20 may be resting on chute 220, reorientation fixture 900, or on any one of the measuring insert ents having a suitable receptacle. The first distance is large enough to straddle the largest circumference smoking article in the preselected range of circumferences.

Next, microprocessor 1000 instructs robot 503 to "close" flanges 501 and 502 so that member 510 and support member 560 are translated together and spaced a second distance apart and notches 515 and 525 are in gripping contact with the smoking article. Preferably, member 510 and support 560 are maintained in a parallel orientation. The second distance and the dimensions and depth of notches 515 and 525 are selected so that in the closed position, notches 515 and 525 will grip securely without deformation the smallest and largest dimensioned smoking articles in the preselected range of articles.

In accordance with the preferred embodiment, spring 540 biases lever 530 against stop 550 so that member 520 is urged parallel to member 510. Thus, for the smallest dimensioned article in a selected range, members 510 and 520 are configured and spaced to grip securely the article in notches 515 and 525 whereby member 520 does not significantly move relative to support 560. For larger dimensioned articles in the selected range, the larger dimension will move member 520 to pivot away from member 510 and compress spring 540. Spring 540 will continue to bias member 520 toward member 510 to group securely article 20, even though the second distance is such that the larger dimensioned article would have been crushed in notches 515 and 525 had member 520 not pivoted relative to support 560. In this manner, spring 540 alters or adjusts the force exerted on article 20 so that article 20 is not crushed.

Advantageously, force altering means 570, and in the preferred embodiment spring 540, permits members 510 and 520 to grip securely a wider variation of smoking article dimensions, specifically circumferences, than would be possible by members 510 and 520 that did not have a force altering means. These improvements in gripping range and performance are important for use in a robotic automated test station where different dimensions present substantial problems, in contrast to a manually conducted system where the operator can intuitively adjust his or her grip to the dimension of the article. In this regard, a plurality of smoking articles to be tested do not inherently have identical physical characteristics. For example, there may be a variation in smoking article circumference from article to article in the same sample set or from one group of article to another. In addition, multiple sample sets may have differently dimensioned like articles. A gripping mechanism for a robotic device in accordance with the present invention is thus able to accommodate the desired variations in dimensions so that the resulting testing data of multiple sets is automatic, reliable, and reproducible without an attendant or need to adjust or change the opposing gripping members.

A pair of gripping members 510 and 520 has been constructed and operated successfully for grasping smoking articles having a circumference dimension selected in the range of from 22 to 25 mm. Referring to FIGS. 15-18, members 510 and 520 were constructed with mirror image tip portions each having a width d of about 14mm (0.56 inches) and a thickness t of about 7mm (0.28 inches). Notches 515 and 525 each has two planar sides cut at 45° angles to the surface, thereby forming an angle α of 90°, the vertex of which extends a depth h of about 4.37mm (0.172 inches) relative to member surfaces 511 and 512. The notch base of depth h is located a distance r of about 7mm (0.280 inches) from the tip of the member, and the opening of the notch has a space s of about 8.76mm (0.345 inches). The distance between surfaces 511 and 521 was fixed at about 2.0mm, which was obtained by manually filing down a shim plate (not shown) to bring faces 511 and 521 sufficiently close together to obtain a good secure grip on the smallest dimensioned article to be processed, e.g. 22mm in circumference, without deflecting members 510 and 520.

Member 520 is configured so that the base of notch 525 is spaced about 30mm (1.22 inches) from the axis of pin 563. The spring force of spring 540 is selected to be a few tens of grams (a few ounces), preferably 80 to 170g (three to six ounces). Of course, the optimum spring force for a given gripper design will be selected based upon the particular geometric distances employed in the design of lever 530, member 520, notches 525 and 515, the spacing between member 510 and 520, the range of motion of the hinge of member 520, and the selected range of differently dimensioned smoking articles to be tested. The magnitude of the spring force will depend in part on the distance of separation between pivot pin 563 and notches 525 and 515 and the distance of separation between pivot pin 563 and spring 540.

In accordance with the invention, other types of opposing gripper members may be used, for example, a member which translates, as opposed to rotates, relative to a support, in combination with a force altering means which allows the member to move relative to the support. Furthermore, the force altering means can

have non-linear characteristics in contrast to the typically linear characteristics of a conventional spring.

Advantageously, robot 503, in accordance with the present invention, provides for an economical and efficient gripping of a variety of conventionally sized smoking articles having a circumference in a preselected range of circumference dimensions, including cigarettes, for efficient manipulation of such articles through a programmed sequence of movements and operations without having to change or adjust manually the robotic gripping elements for differently dimensioned articles in the range.

Referring to FIGS. 1, 2, and 5, one embodiment of length station 200 for measuring the length of an article in accordance with the present invention includes chute 220, camera 230 and bracket 240. Chute 220 is configured to receive one article 20 at top 221 of chute 220, and is provided with a grooved surface having a U-shaped cross sectional shape (see FIG. 5) so that article 20 will advance along chute to stop 222 under gravity. Such a surface also may be concave or V-shaped and may be coated with a low friction material, e.g., Teflon™, or highly polished to minimize friction between article 20 and chute 220. Chute 220 also may comprise two rods or rails that are spaced-apart in parallel (not shown) so that articles 20 will proceed along chute 220 and any tobacco or other particles that come loose from articles 20 do not accumulate in chute 220 or otherwise impede the advance of articles 20.

Camera 230 is mounted on bracket 240 to be positioned a selected distance from chute 220. Camera 230 is preferably an electronic linear array camera for measuring lengths along one axis or dimension. Accordingly, that measuring axis is oriented in parallel with chute 220 so that article 20 will be in the proper orientation for obtaining the length measure. Camera 230 is located a focal distance f from the location article 20 will be at when it is measured, and is provided with a field of view r corresponding to focal distance f .

The measurement may be obtained directly by measuring article length L within the field of view r (see FIG. 6) or more preferably indirectly, by measuring the length a of article 20 that extends into the field of view from one edge of the field of view in the first axis (see FIG. 7). In the indirect mode, one edge of field of view r is located a known distance d from stop 222. Thus, camera 230 obtains the measure 1 of article 20 indirectly by summing the measured length a and the known distance d .

In accordance with a preferred embodiment, camera 230 is configured so that distance d is 75 mm, field of view r is 50 mm, one end of which is spaced 75 mm from stop 222, the other end of which extends to 125 mm from stop 222, providing for a focal distance f selectable in the range of from 225 to 260 mm. Thus, camera 230 is capable of measuring automatically conventional cigarettes having a length from 75 to 125 mm. In embodiments where the image appearing in field of view r of camera 230 is not a true measure, the measure must be converted by the magnification (or reduction) power of the camera lens to obtain the true length dimension.

In an alternate embodiment, stop 222 may be provided with a contact switch (not shown) that produces directly or through microprocessor 1000 an enabling signal to camera 230 when article 20 comes to rest against stop 222. In this embodiment, camera 230 will obtain the length measurement in response to the enabling signal.

Camera 230 is preferably a model HVS 256 camera sold by the Microswitch Division of Honeywell, Englewood, Colorado and has a resolution of 256 pixels in a selected linear dimension or axis. Model HVS 256 is preferably configured to obtain a 50 mm field of view at an accuracy of better than 0.1 mm, preferably 0.05 mm, corresponding to a resolution of better than 0.1 mm, preferably 0.02mm. It is a relatively inexpensive linear array camera, and is thus advantageous to use to measure indirectly the article length.

In making indirect measurements, the first distance d the field of view r and the desired resolution may be adjusted to measure a desired range of acceptable lengths (and variations in lengths) of a large number of different smoking articles.

Also, camera 230 may be moved outwardly and refocused or a different lens used to have a correspondingly increased field of view, or the distance d may be changed as may be appropriate. Other linear array cameras having more pixels, e.g., an EG&G Reticon camera, model LC0120, having 4096 pixels and a resolution of 0.01 mm in one axis, or fewer pixels with a corresponding lower resolution could be used to obtain directly or indirectly the length measurement. Typically linear array cameras having such a higher pixel resolution are, however, substantially more expensive.

Electronic linear array cameras provide almost an instantaneous measure of indirect length a or direct length l depending on the desired configuration. Accordingly, continuous motion length measures are possible. Measures taken while the article is stationary for a period of 0.085 seconds are, however, preferred for optimum resolution.

Camera 230 is preferably adapted to transmit electronically the measured length to microprocessor 1000, which may in turn transmit the data to host computer 1200 for recording and tabulating the data for each article 20 measured.

Subsequent to the length measurement, robot 503 grips article 20 between members 510 and 520 at a distance that is about 65 mm from the filter end for maneuvering article 20 off chute 220 to the selected one

or more workstations for subsequent measurements or tests of the characteristics of the smoking article. Accordingly, chute 220 and stop 222 are suitably located within the range of motion of robot 503 with adequate clearance relating to robot hand 500.

Referring to FIGS. 22-24, fixture 900 for reorienting a smoking article is located on table 12 at a position within reach of robot 503. Fixture 900 provides a location into which an article 20 (shown in phantom lines in FIG. 22) can be deposited by robot 503 so that robot 503 can change its grip on article 20 to a different location. Fixture 900 includes a v shaped, concave surface 910 having a length and two planar surfaces intersecting at an angle B of 110 degrees. Surface 910 is spaced from a stop 920 a distance D2 of about 31.7mm (1.25 inches) to allow members 510 and 520 of robot 503 to grip article 20 without contacting fixture 900. Stop 920 is preferably oriented perpendicular to surface 910 and includes a protrusion 925 which extends from stop 920 so that the end of article 20 is spaced a short distance from stop 920. Surface 910 is preferably at an angle of about 30 degrees relative to table 12 (horizontal) so that article 20 will slide down surface 910 and rest against protrusion 925 of stop 920.

Referring to FIGS. 1, 8, and 9, severing station 300 for severing an article component from the article, more particularly filter rod portion 450 of the article, includes a cutting element 310, aperture 330, air cylinder 340, and ball slide unit 370. Cutting element 310 is used to pass through to sever one smoking article 20 after it is positioned at a selected location in aperture 330 by members 510 and 520 of robot 503. Cutting element 310 is mounted on carriage 360 of ball slide unit 370 between opposing carriage bracket 361 and clamp plate 362. Carriage 360 is mounted on two slide bars 368 and 369, which are mounted in two end blocks 371 and 372 that are respectively supported by spanner bars 373 and 374. Spanner bars 373 and 374 are in turn supported by front side plate 364 and rear side plate 375. Ball slide unit 370 provides a straight, one-dimensional cutting path along which element 310 will travel and may be, for example, model no. DS3-2-C, manufactured by Stelron. The stroke length of air cylinder 340 thus defines the maximum stroke length for element 310, for example, 2.54 cm.

Movement of element 310 is controlled by air cylinder 340 which actuates piston rod 350 to move carriage 360 and carriage bracket 361 in a lateral direction along slide bars 368 and 369. Piston rod 350 is attached to carriage bracket 361 by cylinder block 379. Piston rod 350 is connected to air cylinder 340 and is moved back and forth by air cylinder 340. Air cylinder 340 is preferably a single action device in that a force is applied to extend piston 350 and a spring (not shown) returns piston 350 to its rest position following a lowering of the force. For example, a pressure of 300 kPa (40 psi) of compressed air, applied to compressed air inlet 381 of air cylinder 340, may be used to extend piston 350 to drive carriage 360 so that cutting element 310 passes through smoking article 20. Air cylinder 340 is preferably part no. FOS-04-1.000-3 (Flat 1 air cylinder-single acting-spring return-19mm (3/4 inch) bore-25mm (1 inch stroke)) manufactured and available from Bimba. Air inlet 381 of the cylinder is preferably model no. 11752-1 (hose fitting-#10-32 to 3.2 mm (1/8 inch) I.D. hose) manufactured by Clippard.

Air cylinder 340 is supported by end plate 383 which is also used to separate front side plate 364 from rear side plate 375 and to give overall stability to the cutting unit. Further stability to the cutting unit is provided by support angles 377 and 378 attached to front side plate 364 and rear side plate 375 and table 12.

In one embodiment of the present invention, a solenoid (not shown in the Figures) is used to control delivery of compressed air to inlet 381 to initiate the cutting process. The solenoid is preferably actuated by microprocessor 1000 in response to article 20 being placed in the selected second location. The solenoid also can be controlled manually by a switch mounted in the vicinity of the cutting apparatus.

Alternate devices for moving cutting element 310 in response to article 20 being placed in the second position include stepper motors, linear actuators, rack and pinion mechanisms and similar devices.

Cutting element 310 is preferably a sharp blade, more preferably a conventional single-edged razor blade having a blade length of 3.88 cm. Blade 310 is mounted to carriage 360 between opposing carriage bracket 361 and clamp plate 362. The razor-blade side of clamp plate 362 includes recess 363 which is configured to hold razor blade 310 in the recess at a fixed angle relative to the piston direction. The angle must be sufficient so that the blade severs the smoking article (as contrasted to crushing the article) and passes completely through the cross section of article 20, e.g., 25 to 35 degrees used, more preferably 30 degrees. Additionally, roll pin 366 maybe used to keep razor blade 310 in place during the cutting motion.

In accordance with a preferred use of the present invention, prior to the severing operation, article 20 is preferably placed in orientation station 900 by robot 503. This permits robot 503 to grip article 20 at the mouth end of filter portion 450 between opposing members 510 and 520 and maneuver article 20 axially into aperture 330 extending through front side plate 364 and blade guard 365 to a selected distance or depth. The diameter of aperture 330 is preferably larger than the circumference of the article to be cut to provide tolerance for inserting and extracting articles 20 having a range of circumferences. In a preferred embodiment, the diameter of aperture 330 is 8.33 mm (0.328 inches), or cigarettes having a circumference in the range of 22-25 mm. Aper-

ture 330 can be modified to accommodate smoking articles of other diameters or cross-sectional shapes by replacing front side plate 364 and blade guard 365 with a front side plate and blade guard having an aperture of appropriate dimensions. Preferably, aperture 330 also includes countersink 367 in blade guard 365 to assist in the initial guiding of article 330 into the cutting position.

5 During the cutting operation, robot 503 holds article 20 by its filter end portion 450 with the portion of the article to be severed in the cutting path of blade 310. Once in the second location, air cylinder 340 is actuated to move razor blade 310 to sever article 20 at the designated portion.

Microprocessor 1000 positions robot 503 in response to the previously identified length of the article segment to be severed, e.g., filter portion 450 of a cigarette. Thus, robot 503 is programmed to move members 10 510 and 520 to grip article 320 at, for example, at the mouth end or at midpoint of the filter segment 450, and to insert article 320 to a depth so that razor blade 310 will sever article 320 at a location that is a selected distance from the end of the filter segment to be severed. The selected distance is preferably 2 mm. For example, for a smoking article having a nominal filter length of 27 mm, the robot may be programmed to cut the smoking article at a distance of 29 mm from the mouth end of the filter. Thus, the razor blade will cut through the tobacco and not the filter material.

Advantageously, in accordance with the present invention, severing station 300 provides for severing a filter rod portion from a smoking article so that the automatic test station can perform characterization tests both on the complete article and its filter (or other) component. The precision and accuracy of the cutting operation is determined by the precision and accuracy of the mechanical parts of the computer controlled apparatus as 20 contrasted to an operator's manual ability. The quality of the cut also has been made more reproducible, thereby enhancing statistical analysis and accuracy of tests performed on a plurality of like components severed from a plurality of like smoking articles.

Referring to FIGS. 1, and 10-12, deshredding station 400 for removing tobacco shreds from the severed component includes housing 400, deshredder motor 410, deshredder tool 420, vacuum port 430, and air stream 25 conduit 440. Housing 400 has a motor end 402 and an aperture end 404. Deshredder motor 410, which is mounted in end 402 of housing 400, is used to rotate deshredder tool 420 at a selected speed in the range of 3000 to 4000 rpm, preferably 3600 rpm. Robot 503 inserts filter portion 450 (shown in cross section) in end 404 of housing 400 in axial alignment with motor 410 and tool 420. End 404 has an aperture for receiving filter portion 450. The aperture dimension is preferably selected to receive smoking article filter portions having a circumference in a range of circumferences, e.g., 22-25 mm, and to permit annular air flow into housing 400 when filter portion 450 is inserted. Preferred aperture dimensions are 9 to 10 mm in diameter.

Presenting end 452 of portion 450 is preferably brought within a preselected distance, e.g., 2 mm, of the tip of deshredder tool 420. A stream of high pressure air from source 442 is blown onto presenting end 452 of filter 450 through conduit 440. Rotating deshredder tool 420 may contact the tobacco shreds attached to filter 35 450 that are not loosened by the stream of air, to loosen those shreds not removed by the air stream. Preferably, vacuum port 430 also is provided to exhaust out through a flow path to vacuum 433 any loosened tobacco shreds that have become detached from the end of the filter by the air stream, deshredder tool 420 or both.

Deshredder motor 410 is held in housing 400 by way of screws 412. Attached to the end of the deshredder motor shaft 414 is deshredder tool 420, which is held in place by way of set screw 413. Deshredder tool 420 40 can be made of a hard material, but most preferably it is made out of a hard steel or aluminum alloy, for example, having a black oxide finish.

Referring to FIGS. 11 and 12, tool 120 preferably has two prongs 422 and 423 extending from tip 421 such that tip 421 has a rectangular cross section of width w and length d. Length d corresponds to the diameter in which tip 421 rotates (which is less than the corresponding diameter of the filter portion), for example, in the 45 range of 5 to 5.9mm (0.2 to 0.23 inches), preferably 5mm (0.2 inches). Each prong 424 and 423 preferably is a four sided structure of first dimension w, preferably about 1.1mm (0.045 inches), and second dimension t, preferably about 1.3mm (0.053 inches), such that each prong projects a distance h, preferably about 3.8mm (0.15 inches), from the unmilled rectangular body of tip 421 of tool 420. Prongs 422 and 423 are preferably located at the periphery of distance d, separated by space s of about 2.4mm (0.095 inches).

50 In accordance with an alternate embodiment, deshredder tool 420 may have an alternate motion, for example, a circular back-and-forth motion where the tool rotates half of a revolution before it reverses direction. Tool 420 also may have an alternate tip configuration, for example, more than two prongs, prongs at angles relative to one another, a hook, a scythe, a flat loop, or a spiral or helical section.

Conduit 440, which is preferably simply formed of standard 3.2mm (1/8 inch) outer diameter copper tubing 55 having an inner diameter of 2mm (0.07 inch) terminates adjacent deshredder tool 420. Such tubing is malleable and conduit 440 can be bent, as necessary, to place tip 444 in close proximity to the selected location and deshredder tool 420, directed at presenting end 452 of filler 450. Tip 444 is preferably formed by cutting tube 440 transversely, but may also be provided with a configured shape to provide a nozzle. Source 442 is connected

to conduit 440 and provides an air stream, preferably a high pressure air stream in the range of 70 to 300 kPa (10 to 40 psi), more preferably 150 kPa (20 psi). Source 442 preferably has an on condition and an off condition for regulating air flow depending upon whether or not a filter portion is in position or being brought into position to be deshredded. In accordance with the invention, other types of inert high-pressure gas, for example, nitrogen, and other types of gas jet delivery systems could be used.

Vacuum source 433 is attached to vacuum port 430 of housing 400 by conduit 432. Vacuum source 433 is preferably a 13mm (1/2 inch) diameter house vacuum and has a suction in the range of 380 to 640mm (15 to 25 in.)-Hg, sufficient to exhaust all of the gas provided through conduit 400 and maintain a nominal or slight negative pressure inside housing 400. Vacuum source 433 serves to entrain and to exhaust tobacco shreds which become detached from filter 150 and has an on condition and an off condition depending upon whether or not a filter portion is in position or being brought into position to be deshredded.

In operation, severed filter portion 450 is gripped between opposing members 510 and 520 of robot 503 at a first location, preferably the same position used for the severing operation, and is maneuvered axially into end 404 of housing 400. Robot 503 is provided with information specifying the length of the filter and positions filter 450 to a predetermined selected location corresponding to placing presenting tobacco end 452 of the filter 450 into the deshredding area. In one embodiment, microprocessor 1000 issues an instruction to activate each of deshredder motor 410 to cause tool 420 to rotate, air source 442 to commence air flow through conduit 440, and vacuum source 443 to commence exhausting air through port 430 during or prior to insertion. Thus, these elements are fully operative when filter 450 is positioned in the selected location. As robot 503 brings the end of filter 450 to within a few mm of deshredder tool 420, for example, 1.5 to 2.5 mm, more preferably 2 mm, presenting end 452 becomes subjected to the gas flow which will begin to loosen and remove tobacco shreds even before end 452 is at the selected location.

Robot 503 then holds filter 450 in the selected position for a period of 1 to 4 seconds, more preferably 2 seconds. At the end of this period, microprocessor 1000 issues instructions to deactivate deshredder motor 410, air source 442, and vacuum 433, and to remove the deshredded filter 450 from the deshredder housing 400. In an alternate embodiment, tool 420, source 442 and vacuum 433 may be continuously operating.

Depending on the amount of tobacco shreds to be removed, in the selected location tool 420 may be initially immersed in a relatively thick plug of tobacco shreds thereby to loosen the shreds, or may not be in contact with any shreds. The distance between the tip of tool 420 and the end of filter 450 is selected so that if the tool does not contact any shreds in area 452, the air flow has either removed them or is sufficient to remove them during the time period the filter is maintained at the selected location, and there is an insufficient force to retain the shreds on the filter end to withstand both the air flow and tool 420. In operation, it has been found that the air stream removes most of the tobacco and that the tool is most useful when the presenting portion contains a length of cigarette paper enclosing a plug of tobacco shreds in excess of 2 mm thick. Thus, using deshredding tool 420 to remove all but the last 2 mm of shreds provides for the air stream to remove the remaining shreds and complete the deshredding operation. In addition, deshredding tool 420 may provide a turbulent air stream that facilitates loosening the shreds.

In accordance with the present invention, a plurality of measuring instruments are provided as stations to perform characterization tests on one or more groups of like articles 20 or components, specifically filter portions 450, of articles 20.

Circumference station 600 measures the circumference of one article 20 at a time. Station 600 is mounted at a fixed position on table 12 within the reach of robot 503. Station 600 is preferably a commercial device, model Filtrona Lasemike FLM 200, available from Fidus Insert ent Corporation, Richmond Virginia. The commercial device was modified for use with the present invention by enlarging the sample holder portion to facilitate insertion and extraction of article 20 by robot 503. In accordance with the present invention, robot 503 grips article 20 and maneuvers to insert article 20 axially into the sample holder to a selected depth based on the previously encoded nominal length of article 20 (not shown), whereupon microprocessor 1000 sends a command to device 600 instructing device 600 to read the circumference. Article 20 is then rotated through one revolution as conventional laser measuring techniques are used to take 200 measurements of the diameter of article 20. Device 600 then calculates the circumference of article 20 from the average of the diameter measurements. This data is communicated to microprocessor 1000 and stored, optionally in host computer 1200, for subsequent tabulation and analysis. Following the conclusion of the measurement, robot 503 extracts article 20 from the sample holder and advances it to the next station, in accordance with the program for processing that particular article 20.

PDI station 700 measures the pressure drop and filter ventilation of one article 20 at a time. Station 700 is secured at a fixed location on table 12 within the reach of robot 503. Station 700 is preferably a commercial device, model PDI/ODI available from Fidus Corporation, Richmond Virginia. The commercial device is normally manually operated. For use with the present invention, the device was modified to install conventionally

a suitable number of solenoids and relays so that microprocessor 1000 could control the "manual" operation of the instrument. Thus, to operate the instrument, microprocessor 1000 issues appropriate instructions first to robot 503 to manipulate one article 20 and to insert or release article 20 into the commercial receiving portion of the instrument, and, second, to actuate the relays to drive the solenoids thereby to conduct normally the pressure drop and ventilation measurement procedures.

Similarly, microprocessor 1000 is connected to the data port of the instrument so that the measurements obtained are communicated to microprocessor 1000 for recordation and tabulation. Following the measurement procedures, microprocessor 1000 controls the instrument to eject the article 20 to the receiving portion, whereupon robot 503 is instructed to grip again article 20 and maneuver it to the next station, in accordance with the program for processing that particular article 20.

PDI station 800 measures the filter pressure drop of one filter rod portion 450 at a time. Station 800 is secured at a fixed location on table 12 within the reach of robot 503. Station 800 is preferably a commercial device, model PDI available from Fidus Corporation, Richmond Virginia. The commercial device is normally manually operated. For use with the present invention, the device was modified to install a suitable number of solenoids and relays in a conventional manner so that microprocessor 1000 could control the "manual" operation of the instrument. Thus, to operate the instrument, microprocessor 1000 issues appropriate instructions first to robot 503 to manipulate filter rod portion 450 and to release or insert filter 450 into the commercial receiving portion of the instrument, and, second, to actuate the relays to drive the solenoids thereby to conduct normally the filter pressure drop measurement. Similarly, microprocessor 1000 is connected to the data port of the instrument so that the measurement obtained is communicated to microprocessor 1000 for recordation and tabulation. Following the measurement procedure, microprocessor 1000 controls the insert ent to eject the filter portion 450 to a trash receptacle.

Station 850 measures the filter length of a filter rod portion 450 one at a time. Station 850 is secured at a fixed location on table 12 within the reach of robot 503. Station 850 is preferably a commercial device, model EG-250 available from Ono Sokki Co., Ltd., Tokyo Japan. The commercial device is a digital linear gauge for measuring thicknesses between a movable tip and a fixed base (not shown) having a data communications port for providing measured data and is normally manually operated. For use with the present invention, the device was modified to install an air cylinder and a solenoid in a conventional manner so that microprocessor 1000 could control the "manual" operation of the instrument, specifically the movement of the tip relative to the base. Thus, to operate the insert ent, microprocessor 1000 issues appropriate instructions to robot 503 to manipulate filter rod portion 450 in axial alignment between the tip and the base of the commercial receiving portion of the instrument, and to the solenoid and air cylinder to move the tip to engage the aligned filter portion to conduct the filter length measurement and then to release the filter. Similarly, microprocessor 1000 is connected to the data port of the instrument so that the measurement obtained is communicated to microprocessor 1000 for recordation and tabulation. Following the measurement, microprocessor 1000 instructs robot 503 to grip filter 450, then controls the solenoid and air cylinder and the tip is retracted from the base so that filter portion 450 is removed by robot 503 and maneuvered to the next station, in accordance with the program for processing that particular filter portion 450.

The data collected by microprocessor 1000 are typically transferred to a controller or host computer 1200 for processing. Computer 1200, includes a PC/286 microprocessor device, a model SUN SPARCstation available from Sun Microsystems, Inc. and a conventional database computer. An Ethernet network (not shown) links microprocessor 1000, computer 1200 and the various test instruments for communications therebetween.

Referring to FIG. 1, barcode reader 1300 is connected to computer 1200 for entering sample identification codes for each sample set of a plurality of like articles 20 and creating a database file of the pertinent data regarding the nominal dimensions and characteristics of the articles in that sample. The sample set is inserted into a designated hopper 110 of hopper feeder 100 which is correlated to the bar code given. Database files are shared by computer 1200 and microprocessor 1000 and stored on a software disk that is accessible over the Ethernet network.

Test station 10 in accordance with the present embodiment can test filtered or non-filtered cigarettes and other types of smoking articles having circumferences in the range of 22 to 25 mm and nominal lengths of 80 to 120 mm. Use of the hopper feeder device 100 provides a plurality of hoppers 110, e.g., eighteen, to be filled, each hopper 110 holding up to 30 cigarettes in a given sample set. In the preferred embodiment, test station 10 can be programmed to measure any of article pressure drop, filter ventilation, filter pressure drop, circumference, cigarette length, and filter length on any number of plurality of articles in each sample set in any sequence, provided that tests on a complete article are completed before tests are conducted on a component severed from that article.

Operation of test station 10 in accordance with the present invention begins when the operator loads a sample set into hopper feeder 100, provides the sample set with an identifying bar code, and creates a test

sequence database file for that set in one of host computer 1200 or microprocessor 1000. The database file typically includes the number of articles 20 in the sample set, the nominal length of the articles and their filter portions and other pertinent dimensions of the articles or their components and the test protocol for that sample set, i.e., which tests are to be performed on how many of the articles in that sample set. This information is then
 5 logged in microprocessor 1000 or computer 1200 by the operator at operator workstation 1100 as each sample set is deposited into a designated hopper 110.

The operator can continue loading the system with up to eighteen samples, each sample having a bar code and an associated database. For example, a typical sample set will have twenty-five articles. The operator may instruct that each article will be measured for article length, circumference, and pressure drop, and for filter
 10 ventilation, pressure drop, and length. Alternately, the operator may instruct that only ten of the twenty-five articles will be measured for article length and circumference and filter length, and all twenty-five of the articles will be measured for article pressure drop, filter ventilation, and filter pressure drop. In this regard, robot 503 will not maneuver the other fifteen articles to those stations not selected.

In an alternate embodiment, with appropriate software and memory capacity, it may be possible for the operator program station 10 with a particular order for testing the articles in each sample set, such that the selected ten tests for article length will be taken off the first five articles and the last five articles, whereas the ten tests for filter length will be taken off alternating filter rod portions. Other combinations thus could be created as desired.

Preferably, computer 1200 is used to write the selected barcodes into a "worklist" file that will be used by
 20 microprocessor 1000. After entry of the last test specification, the operator moves to microprocessor 1000 and answers software generated questions which define the station's operating mode. Microprocessor 1000 initializes robot 503 and verifies that the communications network is operational. It then waits for the operator to enter the command at operator workstation 1100 to actually start sample testing. After entering this start command, the operator is then free to perform other tasks.

Microprocessor 1000 transfers the barcode worklist and database specification files from computer 1200 data disk, reads the first barcode from the worklist, extracts the selected test requirements from the corresponding specification file and displays this information on a monitor (e.g., at operator workstation 1100) for operator observation.

A sample of cigarettes from hopper 110 is fed into feeding device 140. The first cigarette is fed from device
 30 140 onto and down chute 220 so that it comes to rest against stop 222 with filter end 450 down, where its length is measured by camera 230. Robot 503 picks up the cigarette by the tobacco end at a distance of about 65 mm from the filter end, rotates it to a filter end up position and sequences it through, for example, station 700 which obtains the article pressure drop and ventilation measurement and station 600 which obtains the article circumference measurement as called for in the specification file. Microprocessor 1000 operates each instrument, reads and records the data, and displays the test values on the system monitor. If no further tests are
 35 to be conducted, robot 503 may move article 20 to a waste receptacle.

For conducting subsequent tests on filter portion 450, robot 503 retrieves article 20 from the last smoking article test station and places and releases article 20 in reorientation fixture 900. Robot 503 then moves hand
 40 500 to rotate and grip article 20 by the filter end. The cigarette is placed in the severing station 300 and filter 450 is cut approximately two mm longer than the nominal length obtained from the specification file. The sheared tobacco rod drops through a chute and into a trash receptacle (not shown). Robot 503 then takes filter 450 to deshredding station 400, where any remaining tobacco is dislodged and vacuumed into a holding tank.

Robot 503 then sequences the filter 450 through stations 850 and 800 for measuring the filter length and filter pressure drop (or vice versa) as indicated in the specification file. The filter pressure drop test is preferably
 45 conducted last. Accordingly, following the measurement, a blast of air blows filter 450 out of the instrument, into a chute which leads to a trash receptacle (not shown). Test station microprocessor 1000 operates each instrument, collects and records the data and displays the data obtained from these instruments on the system monitor.

After all cigarettes in the sample set have been tested, the accumulated data are transmitted in a test data
 50 file to host computer 1200. It has been found that it requires approximately thirty minutes to run a sample of 25 cigarettes through the full complement of tests.

The next sample set in the following hopper 110 is then unloaded into device 140, the bar code and corresponding database file of parameters obtained, and the specified test sequence for the samples in that set is run. This procedure is repeated until the last sample set has been tested. When the data for the final sample
 55 set in the worklist have been transmitted, microprocessor 1000 searches host computer 1200 for another worklist. Additional sample sets can be loaded into hopper feeder 110 and a second worklist containing barcodes having corresponding databases can be created in host computer 1200. If such a second worklist is found, it is transferred to microprocessor 1000 and the testing continues; otherwise, robot 503 is moved to its rest posi-

tion.

The test station of the present invention has a flexible design for optimal use. If host computer 1200 fails, the necessary coding and parameter entry can be entered directly into microprocessor 1000. The data are stored in microprocessor 1000 and sent to the host computer 1200 when communications have been restored. If hopper feeder 100 is not functional, sample sets can be loaded by hand into feeder mechanism 140.

The operator also can bypass a faulty instrument by not requesting a specific test in the test specification file of the database. The operator also may use the test instruments manually, for example, if the robot is not operational or only a select few tests are required. This may be accomplished by inserting a cigarette into an instrument, manually activating the insert ent to conduct the test, and instructing microprocessor 1000 when to read the data obtained by the instrument. The data are typically saved in microprocessor 1000 and sent to host computer 1200 when the testing is completed.

Test station 10 also looks for operational problems while it is running, such as a cigarette not feeding from the hopper, an insert ent blocked by a previously tested cigarette/filter, or a cigarette not being properly placed into an insert ent. When one of these situations is detected, test station 10 tries to correct the problem. The station operating mode specified by the operator determines how test station 10 reacts if it is unable to correct the problem.

When microprocessor 1000 is operating in a mode having an operator in the area and it is unable to correct automatically a problem, it signals the operator that a problem has occurred, stops robot 503 and requests the operator to correct the problem and restart the operation. When restarted, operation resumes where the problem was detected.

When operating in an unattended mode and microprocessor 1000 is unable to correct the problem, it bypasses the problem instrument and goes to the next instrument in the test sequence. Microprocessor 1000 also loads an appropriate failure message into a log file which is transmitted to host computer 1200 along with the test data. This file may be used later to determine what caused the problem.

EXAMPLE

A test station in accordance with the preferred embodiment described above was constructed using the instruments described above. Its operation was compared to a manually operated test station using the same type of instruments.

Three different brands, whose lengths range from 84 to 120 mm, were tested for comparison of data acquired by the robotic test station of the present invention aid by the manual procedure using the conventional instruments. Two sets of samples were taken from the same population of cigarettes; one set was run on the robotic test station and the second set was run on manually operated insert ents. Comparisons were made for cigarette length and circumference, total pressure drop, filter ventilation, filter length and filter pressure drop. The results, which are set forth in Tables I-VI, show that the differences between the robotic test station and the manually operated instruments are less than the standard deviations of the methods.

TABLE ITotal Pressure Drop, mm of H₂O

5	Brand		Robot	Manual	Difference, Δ
	Sample A	$\bar{\kappa}$	126.2	127.0	0.8
		σ	6.2	7.6	
10	Sample B	$\bar{\kappa}$	120.2	120.4	0.2
		σ	4.7	4.3	
	Sample C	$\bar{\kappa}$	133.9	135.7	1.8
		σ	4.7	6.3	

TABLE IIFilter Pressure Drop, mm of H₂O

20	Brand		Robot	Manual	Difference, Δ
	Sample A	$\bar{\kappa}$	68.9	68.8	0.1
		σ	2.9	3.3	
25	Sample B	$\bar{\kappa}$	99.0	100.5	1.5
		σ	5.1	4.2	
	Sample C	$\bar{\kappa}$	103.0	100.9	2.1
		σ	5.1	4.5	

TABLE IIIFilter Length, mm

35	Brand		Robot	Manual	Difference, Δ
	Sample A	$\bar{\kappa}$	26.54	26.83	0.29
		σ	0.12	0.21	
40	Sample B	$\bar{\kappa}$	26.74	26.68	0.06
		σ	0.14	0.18	
	Sample C	$\bar{\kappa}$	31.25	31.38	0.13
		σ	0.32	0.28	

TABLE IVCircumference, mm

Brand		Robot	Manual	Difference, Δ
Sample A	$\bar{\kappa}$	24.78	24.91	0.13
	σ	0.10	0.09	
Sample B	$\bar{\kappa}$	24.95	24.89	0.06
	σ	0.10	0.09	
Sample C	$\bar{\kappa}$	23.12	23.11	0.01
	σ	0.04	0.09	

TABLE VCigarette Length, mm

Brand		Robot	Manual	Difference, Δ
Sample A	$\bar{\kappa}$	99.05	98.89	0.16
	σ	0.21	0.54	
Sample B	$\bar{\kappa}$	83.92	83.89	0.03
	σ	0.22	0.27	
Sample C	$\bar{\kappa}$	119.64	119.59	0.05
	σ	0.18	0.19	

TABLE VIVentilation, %

Brand		Robot	Manual	Difference, Δ
Sample A	$\bar{\kappa}$	0.0	0.0	0.0
	σ	0.0	0.0	
Sample B	$\bar{\kappa}$	21.3	22.1	0.8
	σ	2.1	2.3	
Sample C	$\bar{\kappa}$	26.4	26.4	0.0
	σ	1.7	1.9	

Although the robotic test station requires about twice the time to process samples as the manually operated station, it facilitates continuous and consistent handling of cigarettes and filters and is capable of running a full compliment of tests on 36 sample sets of 25 articles per day. It also provides for assured testing of smoking articles and filters from these article, an improved characterization of the samples, and can operate unattended. Improvements in speed could be obtained by selection of a different robot device and spacing of the various test stations.

```

5  MAIN BATCH FILE FOR ROBOTIC CIGARETTE TEST STATION
   . ACTIVATES A BASIC PROGRAM TO GET OPERATING MODE, THE
   . INVOKES START.BAT, WHICH STARTS THE APPROPRIATE PERL
   . ROUTINE. AFTER PERL ROUTINE EXECUTES, TMPXFER IS RUN TO
   . TRANSFER ANY FILES FROM THE TEMPORARY DIRECTORY TO G,
   . THEN THE BAT FILE LOOPS AROUND AND REPEATS ITSELF.  2/5/90 WBA
10  :
   ECHO OFF
   :LOOP
   CLS
   ECHO WAITING TO START TESTING
   PAUSE
   BASICA INITPROC
15  COMMAND /C START
   command /c TMPXFER
   GOTO LOOP

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SOFTWARE APPENDIX

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1 REM
2 REM ROBOTIC CIGARETTE TEST STATION STARTUP PROCEDURE
3 REM
4 CLS
5 RS=""
6 PRINT
7 PRINT "      1. CALIBRATE LENGTH CAMERA"
8 PRINT "      2. TEST SAMPLES"
9 PRINT
10 INPUT "      ENTER NUMBER OF THE COMMAND TO EXECUTE: ", R#
11 IF R#="1" THEN GOSUB 100 : GOTO 1300 : REM IF TEST COMMAND
12 IF R#="2" THEN GOSUB 200 : GOTO 1300 : REM IF CALIBRATE CAMERA
13 PRINT
14 PRINT "      ***** ERROR IN ENTRY; REPEAT *****"
15 GOTO 30 : REM REPEAT IF IMPROPER COMMAND ENTERED
16 REM
17 REM SET CONFIGURATION AND PERL BATCH FILES FOR CAMERA CALIBRATION
18 REM
19 OPEN "Q", #2, "START.BAT" : REM LOAD START FILE WITH CORRECT PARAMETERS
20 PRINT #2, "COPY MANUAL.SCF PERL.SCF" : REM LOAD MANUAL CONFIGURATION FILE
21 PRINT #2, "PERL.CAL" : REM LOAD PERL BATCH FILE TO RUN
22 CLOSE #2
23 RETURN
24 REM
25 REM IF SAMPLE TESTING SELECTED, GET OPERATION MODE
26 REM
27 RS=""
28 PRINT
29 PRINT "      ENTER A FOR ROBOTIC TESTING OF SAMPLES"
30 PRINT "      ENTER M FOR MANUAL TESTING OF SAMPLES"
31 PRINT
32 INPUT "      ENTER YOUR SELECTION: ", R#
33 IF R#="A" THEN GOSUB 300 : GOTO 1300 : REM IF AUTO TESTING SELECTED
34 IF R#="M" THEN GOSUB 500 : GOTO 1300 : REM IF MANUAL TESTING SELECTED
35 IF R#="D" THEN GOSUB 600 : GOSUB 345 : GOTO 1300 : REM IF DEBUGGING MODE SELECTED
36 PRINT
37 PRINT "      ***** ERROR IN ENTRY; REPEAT *****"
38 GOTO 200 : REM REPEAT IF IMPROPER COMMAND ENTERED
39 REM
40 REM LOAD CONFIGURATION AND PERL BATCH FILES FOR AUTO OPERATION
41 REM
42 OPEN "Q", #2, "START.BAT" : REM LOAD START FILE WITH CORRECT PARAMETERS
43 PRINT #2, "COPY AUTO.SCF PERL.SCF" : REM LOAD ROBOTIC CONFIGURATION FILE

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330 PRINT #2 "PERLATIO" : REM LOAD PERL BATCH FILE TO RUN
340 CLOSE #2
345 R$=""
347 PRINT
10 350 PRINT "    ENTER R IF TEST PARAMETERS ARE TO BE ENTERED REMOTELY
    355 PRINT "    AT THE TEST STATION CONSOLE
    360 PRINT "    ENTER L IF TEST PARAMETERS ARE TO BE ENTERED LOCALLY
    365 PRINT "    AT THE TEST STATION CONSOLE
    370 PRINT
    380 INPUT "    ENTER YOUR CHOICE: ", R$
    390 IF R$="R" THEN GOTO 700 : GOTO : REM IF REMOTE PARAMETER ENTRY SELECTED
    400 IF R$="L" THEN GOTO 800 : GOTO : REM IF LOCAL PARAMETER ENTRY SELECTED
15 410 PRINT
    420 PRINT "    ***** ERROR IN ENTRY; REPEAT *****"
    430 GOTO 340 : REM IF ILLEGAL ENTRY, REPEAT
    440 REM
    450 REM LOAD CONFIGURATION AND PERL BATCH FILES FOR MANUAL OPERATION
    460 REM
    470 OPEN "O", #2, "START.BAT" : REM LOAD START FILE WITH CORRECT PARAMETERS
    480 PRINT #2, "COPY MANUAL.SCF PERL.SCF" : REM LOAD MANUAL CONFIGURATION FILE
20 490 PRINT #2, "PERLMAN" : REM LOAD PERL BATCH FILE TO RUN
    500 CLOSE #2
    510 RETURN
    520 REM
    530 REM LOAD CONFIGURATION AND PERL BATCH FILES FOR DEBUGGING
    540 REM
    550 OPEN "O", #2, "START.BAT" : REM LOAD START FILE WITH CORRECT PARAMETERS
    560 PRINT #2, "COPY AUTO.SCF PERL.SCF" : REM LOAD AUTO CONFIGURATION FILE
25 570 PRINT #2, "PERL" : REM LOAD PERL BATCH FILE TO RUN
    580 CLOSE #2
    590 RETURN
    600 REM
    610 REM IF REMOTE PARAMETER ENTRY SELECTED
    620 REM
30 710 OPEN "O", #2, "OPMODE" : REM LOAD MODE FILE WITH CORRECT MODE
    720 PRINT #2, "REMOTE"
    730 CLOSE #2
    740 PRINT
    750 PRINT "    ***** ENTER TEST PARAMETERS AT WORKSTATION CONSOLE *****"
    760 PRINT "    ***** PLACE SAMPLES IN HOPPER IN THE PROPER ORDER *****"
35 770 GOTO 840
    800 REM
    801 REM IF LOCAL PARAMETER ENTRY SELECTED
    802 REM
    810 OPEN "O", #2, "OPMODE" : REM LOAD MODE FILE WITH CORRECT MODE
    820 PRINT #2, "LOCAL"
    830 CLOSE #2
    840 R$=""
40 845 PRINT
    850 PRINT "    BE SURE ROBOT IS IN PROPER POSITION FOR INITIALIZATION"
    860 PRINT "    BE SURE INSTRUMENTS ARE IN PROPER STATE FOR START UP"
    870 INPUT "    ENTER R WHEN READY TO RUN: ", R$
    880 IF R$="R" THEN GOTO 900 : REM IF READY TO RUN
    890 PRINT
    895 PRINT "    ***** ERROR IN ENTRY; REPEAT *****"
45 900 GOTO 840 : REM IF ILLEGAL ENTRY, REPEAT
    910 RETURN
1000 SYSTEM
1010 END

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PERL. BAT

COPY AUTO.SCF PERL.SCF

cls

echo LOADING PERL V16D

10

c:perl16d =10000 -p48000 -d32000 -rSTARTPOS

PERCAL. BAT

COPY MANUAL.SCF PERL.SCF

cls

echo LOADING PERL V16D

15

c:perl16d =10000 -p48000 -d32000 -rCAMCAL

PERLAUTO. BAT

COPY AUTO.SCF PERL.SCF

cls

echo LOADING PERL V16D

20

c:perl16d =10000 -p48000 -d32000 -rSTARTUP

PERLMAN. BAT

COPY MANUAL.SCF PERL.SCF

cls

echo LOADING PERL V16D

25

c:perl16d =10000 -p48000 -d32000 -rMANUAL

COPY X1.SCF PERL.SCF

cls

echo LOADING PERL V16D

30

c:perl16d =10000 -p48000 -d32000 -rSTARTPOS

TMPXFER. BAT

```

: THIS PROCEDURE CHECKS FOR FILES IN THE TEMP STORAGE DIRECTORY
: \LINK\WORK\TMP. IF FILES FOUND THERE, A CHECK IS MADE TO SEE IF
: THE NETWORK IS OPERATIONAL. IF IT IS OPERATIONAL, THE FILES ARE
: TRANSFERED TO G: FOR WORKSTATION USE AND DELETED FROM THE
: \LINK\WORK\TMP DIRECTORY. 1/30/90 WSA

```

35

rem echo off

if not exist \link\work\tmp*.dat goto finish

rfsping pm14

40

if errorlevel 1 goto finish

copy \link\work\tmp*.dat g:

del \link\work\tmp*.dat

:finish

45

procedure startpos

use robot

rem init robot

speed 5

nest1

.peed 2

GRIP7725

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end procedure

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PROCEDURE CAMCAL
! THIS PROCEDURE IS USED TO CALIBRATE THE ROD LENGTH CAMERA.
! A WAKE-UP MESSAGE IS SENT TO THE CAMERA FIRST. THEN, IT TURNS ON THE
! INTERNAL LIGHT, UNTIL THE OPERATOR ENTERS Q ON THE CONSOLE. THE CAMERA
! THEN STARTS TAKING MEASUREMENTS, DISPLAYING THEM ON THE SCREEN AND ON
10 ! THE MANUAL CONTROL STATION DISPLAY. THIS CONTINUES UNTIL THE OPERATOR
! AGAIN ENTERS Q ON THE CONSOLE, AFTER WHICH THE PROGRAM EXITS BACK TO DOS
!

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    DEFINE CL$ AS CLEN
    CLEAR
    CL$="XMZ" ! SEND WAKE UP MESS TO CIG LEN GAUGE
    SEND CL$
15    RECEIVE CL$
    G$=""
    DISPLAY
    DISPLAY "THE CENTER LEDS ON THE CAMERA SHOULD NOW BE LIT."
    DISPLAY "ENTER Q WHEN FINISHED."
    CL$="XDF" ! DISPLAY FOCUS ON LEDS
    SEND CL$
20    REM RECEIVE CL$
    G$=""
    WHILE G$<>"Q"
        G$=READKEY$
    END WHILE
    CL$="XDS00" ! SET MESS TO DISPLAY FIELD OF VIEW ON LEDS
    SEND CL$
25    REM RECEIVE CL$
    DISPLAY
    DISPLAY "USE ADJUSTMENTS TO CALIBRATE CAMERA, USING SHORT AND LONG RODS."
    DISPLAY "ENTER Q WHEN FINISHED."
    G$=""
    WHILE G$<>"Q" ! WAIT FOR Q TO BE ENTERED
        REM GETLEN ! READ AND CALCULATE LENGTH
30        REM CL$="XTL9"
        REM SEND CL$
        REM RECEIVE CL$
        REM CL$="T"
        REM SEND CL$
        REM RECEIVE CL$
    REM CLEND$=CL$
35    GETLEN
    REM MAN1$="LENGTH = "+CLEND$
    REM DISMANUL ! DISPLAY ON MANUAL PENDANT
    DISPLAY " ROD LENGTH = "+CLEND$+" ENTER Q IF FINISHED."
    SET TIMER 1 FOR 2 SECONDS
    WAIT FOR TIMER 1
    G$=READKEY$ ! CHECK KEYBOARD FOR INPUT
40    END WHILE
    MAN1$=""
    DISMANUL ! CLEAR DISPLAY
    SYSTEM
END PROCEDURE

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PROCEDURE STARTUP
GRIP7725 ! SET GRIP POS 7,7,25
CLEAR
DEFINE CR$ AS CPDI ! CIG RTD PORT
10  DEFINE D$ AS DIL ! DILUTION PORT
    DEFINE C$ AS CIRC ! CIRCUMFERENCE PORT
    DEFINE F$ AS FLGAUGE ! FILTER LENGTH PORT
    DEFINE CL$ AS CLEN ! CIG LENGTH PORT
    DEFINE FR$ AS FPD1 ! FILTER RTD PORT
    DISPLAY
    CLEAR
15  ERRSTOP$="F" ! SET FLAG TO NOT STOP ON ERRORS
    MAIN ! EXECUTE MAIN LOOP
    OPEN
    NEST1 ! MOVE TO START POSITION
    SYSTEM ! EXIT PERL AFTER SAMPLES TESTED
    REM PRINT " END OF STARTUP PROC ";TIME$
    END PROCEDURE
20

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PROCEDURE MAIN
  REM THIS IS THE MAIN PROCEDURE FOR THE ROBOTIC CIGARETTE TEST STATION. IT
  REM CHECKS TO SEE IF THE TEST PARAMETERS ARE TO BE ENTERED LOCALLY OR
  REM REMOTELY. IF LOCAL, THE PARAMETER ENTRY PROCEDURE IS EXECUTED. IF IN
  REM REMOTE, THE OPERATION OF THE NETWORK IS CHECKED. IF NOT OPERATIONAL, THE
10  REM OPERATOR IS ALLOWED TO ENTER THE LOCAL ENTRY MODE. IF OPERATIONAL, THE
  REM REMOTE DRIVE IS CHECKED FOR THE PRESENCE OF A WORKLIST. IF FOUND, THE
  REM WORKLIST AND THE SPECFILES ARE TRANSFERRED FROM E: AND F: RESPECTIVELY,
  REM TO C:\LINK\SPEC\.. IN EITHER LOCAL OR REMOTE MODE, AFTER THE TEST SPECS
  REM HAVE BEEN FOUND, THE OPERATOR IS PROMPTED TO ENTER R WHEN READY TO START
  REM TESTING. AFTER EACH SAMPLE IS COMPLETED, THE DATA IS TRANSFERRED TO
  REM STORAGE. THIS IS REPEATED UNTIL ALL SAMPLES HAVE BEEN TESTED.
15  REM 5/23/90 WBA
  REM PRINT " START OF MAIN PROC ";TIME$
  RLCTR%=0 ! REMOTE LOOP COUNTER
  RL$="R" ! SET TO REMOTE SO INIT BELOW WILL RUN IN WHILE LOOP BELOW
  Y$=""
  IF RLCTR%=0 THEN ! DO ONLY IF FIRST TIME IN REMOTE LOOP
    WHILE Y$() "Y"
20      IF WLFLAG=1 THEN ! WORKLIST FLAG SET IN GET_DATA
        DISPLAY " ALL WORKLIST TEST HAVE BEEN COMPLETED "
      END IF
      DISPLAY
      DISPLAY " YOU ARE NOW IN THE AUTOMATIC MODE OF OPERATION "
      SET TIMER 1 FOR 2 SECONDS
      WAIT FOR TIMER 1
25      READ MODE$ FROM "OPMODE" ! CHECK PARAMETER ENTRY MODE
      CLOSE "OPMODE"
      IF MODE$="LOCAL" THEN ! IF IN LOCAL PARAMETER ENTRY MODE
        RL$="L"
        Y$="Y"
      ELSE
        ! IF IN REMOTE PARAMETER ENTRY MODE
30      IF MODE$="REMOTE" THEN ! IF IN REMOTE MODE
        RL$="R" ! SET REMOTE FLAG
        DISPLAY
        DISPLAY " STANDBY FOR CHECK OF NETWORK OPERATION:"
        DISPLAY
        CHECKLNK ! SEE IF NETWORK OPERATIONAL
        IF LINK$="UP" THEN ! IF NETWORK OPERATIONAL
          Y$="Y"
35        ELSE
          DISPLAY
          DISPLAY " ***** NETWORK IS NOT OPERATIONAL *****"
          DISPLAY " TEST PARAMETERS CAN NOT BE READ FROM WORKSTATION"
          DISPLAY
          DISPLAY " DO YOU WISH TO ENTER PARAMETERS AT THE TEST STATION";
          INPUT " (Y OR N) " ;Y$
          IF Y$="Y" THEN
40            RL$="L" ! SET FLAG FOR LOCAL PARAMETER ENTRY
          ELSE
            Y$="Y" ! SET FLAG TO EXIT LOOP
            DISPLAY
            DISPLAY " EXIT TEST ROUTINE"
            END IF
          END IF
45        ELSE
          DISPLAY MODE$
          SET TIMER 1 FOR 5 SECONDS
          WAIT FOR TIMER 1
          END IF
        END IF
50      DISPLAY
      END WHILE
    END IF
  END IF
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IF RL$="L" THEN ! IF LOCAL PARAMETER ENTRY
  CLEAR
  DISPLAY
  DISPLAY " YOU ARE IN THE LOCAL TEST PARAMETER ENTRY MODE"
  DISPLAY
  Y$="N"
  READ WLST$ FROM "WLFILE" ! SEE IF WORKLISTS ALREADY EXISTS
  CLOSE "WLFILE"
  IF WLST$="WORKLIST FOUND" THEN ! IF WORKLIST IS PRESENT
    DISPLAY
    DISPLAY " A WORKLIST HAVING THE FOLLOWING BARCODES WAS FOUND:"
    WHILE WLST$(<)"END OF WORKLISTS" ! UNTIL ALL BARCODES HAVE BEEN READ
      READ WLST$ FROM "WORKLIST" ! READ BARCODE
      DISPLAY WLST$
    END WHILE
    CLOSE "WORKLIST"
    Y$=""
    WHILE Y$=""
      DISPLAY
      DISPLAY " DO YOU WANT TO RUN THESE BARCODES NOW (Y OR N)?"
      INPUT " (N WILL DELETE THESE BARCODES) ",Y$
    END WHILE
  END IF
  IF Y$="N" THEN
    GETPARAM ! GET TEST PARAMETERS LOCALLY
  END IF
  WLFLAG=1 ! SET FLAG TO LOOK FOR WORKLISTS
ELSE ! IF REMOTE PARAMETER ENTRY
  IF LINK$="UP" THEN ! IF NETWORK OPERATIONAL
    WLFLAG=1 ! SET FLAG TO LOOK FOR WORKLISTS
  END IF
  ND IF
  ERRMODE ! GET ERROR RECOVERY MODE, ATTENDED OR UNATTENDED
  WHILE WLFLAG=1 ! WHILE WORKLISTS ARE PRESENT
    RLCTRX=0
    IF MODE$="REMOTE" THEN ! IF IN REMOTE MODE
      CHECKLNK ! SEE IF NETWORK STILL ACTIVE
      IF LINK$="UP" THEN ! IF NETWORK STILL ACTIVE
        DISPLAY " TRANSFERING SPEC FILES TO THE TEST STATION:"
        DDS CHKWLST ! SEE IF WORKLISTS PRESENT
        READ WLST$ FROM "WLFILE"
        IF WLST$(<)"NO WORKLISTS FOUND" THEN
          WRITE WLST$ TO "WLERASE.BAT" ! WRITE WORKLIST FILE NAME TO ERASE
          READ WLST$ FROM "WLFILE"
          WRITE WLST$ TO "WLERASE.BAT" ! WRITE WORKLIST FILE NAME TO RENAME
          CLOSE "WLERASE.BAT"
          DDS TRANSFER ! TRANSFER FROM NETWORK TO TEST STATION
        END IF
      END IF
      CLOSE "WLFILE"
    END IF
    END IF
    GETWLST ! SEE IF WORKLIST PRESENT IN LINK\SPEC\ DIRECTORY
    WHILE SPECFLAG=1 ! WHILE BARCODES ARE PRESENT
      GET DATA ! CALL PROC FOR RETREIVING TEST DATA
      IF SPECFLAG=1 THEN ! IF BARCODE FOUND
        SAMCTX = SAMNOX ! SET SAMCTX TO LARGEST # SAMPLES TO BE RUN
        CLEAR ! CLEAR SCREEN
        ALARM ON
        SET TIMER 1 FOR 1 SECOND
        WAIT FOR TIMER 1 ! SOUND ALARM JUST BEFORE ROBOT BEGINS MOVING
        ALARM OFF
        FILLHOPR ! MOVE SAMPLES FROM MAIN HOPPER TO FEED HOPPER
        IF RLCTRX=1 THEN ! IF FIRST BARCODE IN WORKLIST
          WRITE BARCODE$ TO "USEDLIST" ! RECORD CODE AS BEING USED
        ELSE
          APPEND BARCODE$ TO "USEDLIST"

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END IF
CLOSE "USEDLIST"
DISHEADR ! DISPL DATA HEADER
PROBCTR%=0 ! CLEAR TROUBLE MESSAGE COUNTER
WHILE SAMCT% > 0
10  DLINE%=SAMNO%-SAMCT% ! CALCULATE SAMPLE # FOR DATA DISPLAY LINE
    DISPLAY ! CLEAR ANY PREVIOUS MESSAGES FROM THIS LINE
    REM    DISPLAY
    REM    CURSOR (DLINE%*17)+7,1
    IF DLINE%=17 THEN ! IF WRAPPING DISPLAY AROUND TO TOP
        DISPLAY ! CLEAR THIS LINE
        CURSOR (DLINE%*17)+7,1 ! MOVE BACK UP TO LINE
15  REM    END IF
    DISPLAY DLINE%+1; ! DISPLAY SAMPLE NUMBER
    GSAMPLE ! GET SAMPLE AND RECORD LENGTH, IF REQUIRED
    IF ((CFLAG = 1) AND (TST2%>0)) OR ((DFLAG=1) AND (TST4%>0)) THEN
        CRTDCHK ! SEE IF INSTRUMENT IS EMPTY
        IF (TST2%>0) OR (TST4%>0) THEN ! IF INSTRUMENT IS READY
            IF FAULT%<>"S" THEN ! IF NOT SKIPPING THIS CIGARETTE
20          TOTRTD ! CALL TOTAL RTD PROCEDURE
            END IF
        END IF
    END IF
    IF (CFLAG = 1) AND (TST3%>0) THEN
        CIR ! CALL CIRCUMFERENCE PROCEDURE
    END IF
    IF ((TST5% > 0) OR (TST6% > 0)) AND (SIH%=1) THEN
25      ! IF FLEN OR FRTD REQUIRED AND SAMPLE PRESENT IN HAND
        FCO ! CALL FILTER CUT OFF PROCEDURE
    ELSE ! IF NO OTHER TEST REQUIRED
        SAFPOS ! DISCARD CIGARETTE
        OPEN
    END IF
    IF (FLFLAG = 1) AND (TST5%>0) AND (SIH%=1) THEN
30      FLEN ! CALL FILTER LENGTH PROCEDURE
    END IF
    IF (FRFLAG = 1) AND (TST6%>0) AND (SIH%=1) THEN
        FRTDCHK ! SEE IF INSTRUMENT IS EMPTY
        IF (TST6%>0) THEN ! IF INSTRUMENT IS READY
            IF FAULT%<>"S" THEN ! IF NOT SKIPPING THIS FILTER
35          FRTD ! CALL FILTER RTD PROCEDURE
            END IF
        END IF
    END IF
    SAMCT% = SAMCT% - 1
    IF FAULT%="A" THEN ! IF ABORTING TESTING OF ALL SAMPLES
        ABORTRUN
    END IF
    R%=READKEY% ! SEE IF KEY ENTERED
    IF R%<>" " THEN ! IF KEY ENTERED
        WHILE R%<>" " ! CLEAR KEYBOARD BUFFER
            R1%=R% ! SAVE LAST KEY INPUT
            DISPLAY R%;
            R%=READKEY%
        END WHILE
        IF R1%="P" THEN ! IF PAUSE KEY ENTERED
45          DISPLAY
            ERRSTOP%="T" ! SET FLAG TO PAUSE IN ERRRESP
            ERRRESP ! SIGNAL STOP AND GET OPERATOR RESPONSE TO CONTINUE
            ERRMODE ! ALLOW ERROR MODE TO BE CHANGED, IF NEEDED
        END IF
    END IF
    END WHILE
50  CLRHOPR ! REMOVE ANY SAMPLES LEFT
    OPEN
    CURSOR 20,1 ! MOVE CURSOR

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      IF DLINE%>0 THEN ! IF DATA TAKEN
      DAT! CALL PGM TO COLLECT DATA AND STORE IN "BARCODE.DAT"
      END IF
      PCHECK ! SEE IF PAUSE ENTERED
      DISPLAY
10    END IF ! END IF BARCODE FOUND
      END WHILE ! BARCODES ARE PRESENT
      IF MODE$="REMOTE" THEN
      CMD$="NO CODES"
      WRITE CMD$ TO "USEDLIST" ! CLEAR USED CODE LIST
      CLOSE "USEDLIST"
      END IF
15    END WHILE ! WORKLISTS ARE PRESENT
      END PROCEDURE

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PROCEDURE CHECKLNK

! THIS PROCEDURE CHECKS THE STATUS OF THE NETWORK AND SETS LINK# TO
 ! INDICATE THAT STATUS. THE BASIC PROGRAM "NETCHECK" IS CALLED. IF
 ! THE NETWORK IS OPERATIONAL, THE BASIC PROGRAM RETURNS IMMEDIATELY.
 10 ! IF THE NETWORK IS NOT OPERATIONAL, THE BASIC PROGRAM RETURNS AFTER
 ! A TIMEOUT PERIOD. THE STATUS OF THE NETWORK IS RETURNED IN THE FILE
 ! "LINKSTAT.DAT" AND IS SAVED IN LINK#.

DOS NETCHECK ! CHECK THE NETWORK STATUS
 READ LINK# FROM "LINKSTAT.DAT" ! READ THE STATUS OF THE NETWORK
 CLOSE "LINKSTAT.DAT"
 15 REM DISPLAY LINK#
 REM SET TIMER 1 FOR 2 SECONDS
 REM WAIT FOR TIMER 1
 END PROCEDURE

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NETCHECK.BAT
: THIS BATCH FILE CHECKS THE NETWORK SERVER TO SEE IF IT IS OPERATIONAL
: OPERATIONAL. IT WRITES THE STATUS OF THE NETWORK TO THE FILE
: LINKSTAT.DAT 1/19/98 WBA
:
10 :
: go off
: ping pm14
: if errorlevel 1 goto netdown
:netup
: @echo UP>linkstat.dat
: @goto finish
15 :netdown
: @echo DOWN>linkstat.dat
:finish
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CHXWLST.BAT
ECHO OFF
: ROTS BAT FILE TO ACTIVE WORKLIST SEARCH PROGRAM FF BASIC
BASICA WORKLIST

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PROCEDURE ERRMODE
  REM THIS PROCEDURE ALLOWS THE OPERATOR TO SPECIFY WHETHER THE TEST STATION
  REM IS TO OPERATE IN THE ATTENDED OR THE UNATTENDED MODE. IN GENERAL,
  REM WHEN THE ROBOT DETECTS AN OPERATIONAL PROBLEM, IT TRIES TO CORRECT THE
  REM PROBLEM. IF IT CANNOT, IT SIGNALS THE OPERATOR AND STOPS WHEN IN THE
  REM ATTENDED MODE. THE OPERATOR CAN THEN CORRECT THE PROBLEM AND TELL THE
  REM ROBOT TO CONTINUE. IN THE UNATTENDED MODE, IT CONTINUES ON, BUT SKIPS
  REM THE INSTRUMENT WHICH IT THINKS HAS THE OPERATIONAL PROBLEM. 3/6/92 WEA
  R$=""
  WHILE R$=""
    15  DISPLAY
    DISPLAY
    INPUT "      DO YOU WANT TO STOP WHEN AN ERROR IS DETECTED (Y OR N)";R$
    CASE R$
      IS "Y":
        ERRSTOP$="T" ! SET FLAG TO STOP ON ERRORS
      IS "N":
        20  ERRSTOP$="F" ! SET FLAG TO CONTINUE ON ERRORS
        DEFAULT:
          R$="" ! RESET TO STAY IN LOOP
    END CASE
  END WHILE
  R$=""
  25  WHILE R$(<>)"R"
    DISPLAY
    INPUT "      ENTER R WHEN READY TO RUN: ",R$
    DISPLAY
  END WHILE
END PROCEDURE

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10 10 REM
20 20 REM "WORKLIST PROGRAM"
30 30 REM THIS PROGRAM SEARCHES FOR A WORKLIST FOR THE ROBOTIC CIGARETTE TEST
40 40 REM STATION. A WORKLIST CONTAINS THE BARCODES OF THE SAMPLES TO BE TESTED,
50 50 REM AND IN THE ORDER TO BE TESTED. A WORKLIST HAS THE NAME "WMMDDYY.EXT",
60 60 REM WHERE MMDDYY IS THE MONTH, DAY, AND YEAR THE WORKLIST WAS ENTERED INTO
70 70 REM THE WORKSTATION. "EXT" IS THE SEQUENCE NUMBER OF THE WORKLIST, STARTING
80 80 REM AT "000" AND GOING UP TO "MAXEXT". THE PROGRAM FIRST READS THE FILE
90 90 REM "LASTLIST", TO FIND THE DATE OF THE LAST WORKLIST USED. IT THEN STARTS
100 100 REM SEARCHING THE WORKSTATION DIRECTORY FOR A WORKLIST HAVING THAT NAME.
110 110 REM IT CONTINUES TO SEARCH, INCREMENTING THE WORKLIST NAME AND/OR EXTENSION
120 120 REM AS NEEDED, UNTIL A WORKLIST IS FOUND, OR UNTIL THE CURRENT DATE HAS BEEN
130 130 REM USED. IF A WORKLIST IS NOT FOUND, THE MESSAGE "NO WORKLISTS FOUND" IS
140 140 REM STORED IN THE FILE "WLFILE", AND THE PROGRAM EXITS. IF A WORKLIST IS
150 150 REM FOUND, THE BARCODES ARE TRANSFERRED TO THE FILE "WORKLIST". THE NAME OF
160 160 REM THE WORKLIST IS SAVED IN "WLFILE" FOR RENAMING BY THE PERL PROGRAM AFTER
170 170 REM THE SAMPLES HAVE BEEN TESTED. THE SPEC FILES ARE SAVED IN THE FILE
180 180 REM "TRANSFER.BAT", FOR TRANSFER FROM THE NETWORK TO A HOLDING DIRECTORY IN
190 190 REM THE TEST STATION PC. THE NAME OF THE WORKLIST IS ALSO SAVED IN THE FILE
200 200 REM "LASTLIST" FOR STARTING THE NEXT WORKLIST SEARCH. 3/16/90 WBA
210 210 REM
220 220 CLOSE
230 230 ON ERROR GOTO 920
240 240 ON TIMER (3) GOSUB 980 : REM 3 SECOND TIMER FOR DISPLAY OF BARCODE
250 250 DA$=DATE$
260 260 M$=LEFT$(DA$,2) : CURMON=VAL(M$)
270 270 D$=RIGHT$(DA$,7)
280 280 D$=LEFT$(D$,2) : CURDAY=VAL(D$)
290 290 Y$=RIGHT$(DA$,4) : CURYR=VAL(Y$)
300 300 OPEN "\PERL\LASTLIST" FOR INPUT AS #1 : REM GET LAST WORKLIST NAME USED
310 310 INPUT #1, LASTLIST$
320 320 CLOSE #1
330 330 M$=LEFT$(LASTLIST$,2) : REM PRINT M$
340 340 D$=MID$(LASTLIST$,3,2) : REM PRINT D$
350 350 Y$=MID$(LASTLIST$,5,4) : REM PRINT Y$
360 360 DAY=VAL(D$) : REM CONVERT DAY TO NUMBER
370 370 MON=VAL(M$) : REM CONVERT MONTH
380 380 YR=VAL(Y$) : REM CONVERT YEAR
390 390 Y$=RIGHT$(Y$,2) : REM PRINT Y$
400 400 OPEN "\PERL\WORKLIST" FOR OUTPUT AS #2
410 410 MAXEXT=50 : REM MAX. EXTENSION NUMBER FOR WORKLIST FILES
420 420 IX=1
430 430 EXT=0 : REM INITIALIZE FILE EXTENSION
440 440 LASTLIST$=M$+D$+Y$ : REM FORM WORKLIST ROOT NAME
450 450 WL$="W"+LASTLIST$ : REM FORM WORKLIST ROOT NAME FROM MONTH, DATE, YEAR
460 460 TL$="T"+LASTLIST$ : REM FORM USED WORKLIST NAME
470 470 PRINT M$+"/"+D$+"/"+Y$ : REM DISPLAY DATE BEING SEARCHED FOR
480 480 IF CURYR(YR GOTO 800 : REM IF TODAY'S YR (SEARCH YR, STOP
490 490 IF (CURMON(=MON) AND (CURDAY(DAY) AND (YR=CURYR) GOTO 800
500 500 WHILE EXT<MAXEXT
510 510 EXT$=STR$(EXT) : REM FORM FILE EXTENSION
520 520 EXT$="00"+RIGHT$(EXT$,LEN(EXT$)-1)
530 530 EXT$=" "+RIGHT$(EXT$,3)
540 540 P$=WL$+EXT$ : REM FORM COMPLETE FILE NAME
550 550 OPEN "E:\ "+P$ FOR INPUT AS #1
560 560 Q$=TL$+EXT$ : REM FORM COMPLETE USED FILE NAME
570 570 PRINT P$
580 580 OPEN "\PERL\WLFILE" FOR OUTPUT AS #3
590 590 PRINT #3, "DELETE "+D$ : REM SAVE WORKLIST FILE NAME TO DELETE
600 600 PRINT #3, "RENAME "+P$+" "+Q$ : REM SAVE WORKLIST FILE NAME TO RENAME
610 610 CLOSE #3
620 620 OPEN "\PERL\TRANSFER.BAT" FOR OUTPUT AS #3
630 630 IF EOF(1) THEN CLOSE #1 : CLOSE #3 : GOTO 740
640 640 INPUT #1, BARCODE$
650 650 PRINT #3, BARCODE$
660 660 PRINT #3, "COPY "+BARCODE$+" .SPEC\LINK SPEC" : REM SAVE SPEC FILE NAME TO COPY

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570 PRINT #3,"DEL F:\\"+E$+CODE$+".SPE" : REM SAVE SPE FILE NAME TO DELETE
580 PRINT "#";IX;"BARCODE=" ;BARCODE$
590 TIMER ON : REM ACTIVATE DELAY TIMER WHILE CODE DISPLAYED
700 GOTO 700 : REM WAIT FOR TIMER TO EXPIRE
10 10 TIMER OFF : REM STOP TIMER
720 IX=IX+1 : REM INCREMENT CODE COUNTER
730 GOTO 530
740 IF IX > 1 THEN EXT=MAXEXT% : REM IF BARCODE FOUND IN WORKLIST
750 EXT=EXT + 1 : REM INCREMENT EXTENSION
760 WEND
770 IF IX > 1 THEN GOTO 530 : REM IF BARCODES FOUND IN WORKLIST
15 780 GOSUB 1000 : REM INCREMENT WORKLIST NAME TO NEXT DATE
790 GOTO 430 : REM REPEAT SEARCH
820 OPEN "\PERL\WLFIL" FOR OUTPUT AS #3
810 PRINT #3,"NO WORKLISTS FOUND": CLOSE #3
820 GOTO 900
830 PRINT #2,"END OF WORKLISTS" : REM INDICATE END OF WORKLIST
840 CLOSE #2
20 850 Y$=STR$(YR) : Y$=RIGHT$(Y$,LEN(Y$)-1)
850 LASTLIST$=M$+D$+Y$ : REM FORM NAME OF LAST WORKLIST FOUND
870 OPEN "\PERL\LASTLIST" FOR OUTPUT AS #2
880 PRINT #2,LASTLIST$ : REM SAVE NAME OF LAST WORKLIST FOUND
890 CLOSE #2
900 CLOSE
910 SYSTEM
920 REM
25 930 REM ERROR HANDLING SUBROUTINE
940 REM
950 IF (ERR=53) THEN RESUME 750 : REM IF FILE DOES NOT EXIST
960 IF (ERR=55) THEN PRINT " FILE ALREADY OPEN ":RESUME NEXT
970 PRINT "ERROR";ERR : RESUME NEXT
980 RETURN 710 : REM RETURN AFTER DELAY FOR DISPLAYING BARCODE
990 END
30 1000 REM
1010 REM INCREMENT WORKLIST NAME TO NEXT DATE
1020 REM
1030 DAY=DAY+1 : REM INCREMENT TO NEXT DAY
1040 IF (DAY > 29) GOTO 1160 : REM IF NOT END OF MONTH, CONTINUE SEARCH
1050 IF (MON=2) THEN GOTO 1100 : REM IF NOT FEBRUARY, CONTINUE SEARCH
1060 IF ((YR MOD 4)=0) AND (DAY=29) GOTO 1160 : REM IF 2/29 OF LEAP YEAR
35 1070 MON=3 : REM SET MONTH TO MARCH IF NOT 2/29 OF LEAP YEAR
1080 DAY=1 : REM RESET DAY
1090 GOTO 1160 : REM CONTINUE SEARCH
1100 IF DAY > 31 GOTO 1160 : REM IF NOT END OF MONTH
1110 IF (MON=1) OR (MON=3) OR (MON=5) OR (MON=7) OR (MON=8) OR (MON=10) OR (MON=
12) GOTO 1140 : REM IF JAN, MAR, MAY, JUL, AUG, OCT, DEC
1120 GOSUB 1190
40 1130 GOTO 1160
1140 IF DAY > 32 GOTO 1160 : REM IF NOT END OF MONTH
1150 GOSUB 1190 : REM IF END OF MONTH, INCREMENT MONTH
1160 D$=STR$(DAY) : D$="0"+RIGHT$(D$,LEN(D$)-1) : D$=RIGHT$(D$,2)
1170 M$=STR$(MON) : M$="0"+RIGHT$(M$,LEN(M$)-1) : M$=RIGHT$(M$,2)
1180 RETURN
1190 REM
45 1200 REM INCREMENT MONTH AND YEAR
1210 REM
1220 DAY=1
1230 MON=MON+1
1240 IF MON=13 GOTO 1290 : REM IF NOT DECEMBER
1250 YR=VAL(Y$)
1260 YR=YR+1 : REM INCREMENT YEAR
1270 Y$=STR$(YR) : Y$="0"+RIGHT$(Y$,LEN(Y$)-1) : Y$=RIGHT$(Y$,2)
50 1280 MON=1 : REM SET MON TO JAN
1290 RETURN

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PROCEDURE GETWKLIST
! THIS PROCEDURE IS USED WHEN IN THE REMOTE PARAMETER ENTRY MODE, TO LOOK
! FOR THE WORKLIST, AND IF FOUND, TO TRANSFER IT FROM THE NETWORK SERVER TO
! A DIRECTORY ON THE PC, WHERE IT CAN BE USED BY THE TEST STATION. IT ALSO
10 ! TRANSFERS THE TEST SPEC FILES. 1/19/90 WEA

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IF RLCTRX=0 THEN ! IF FIRST TIME THRU LOOP
  CLEAR
  REM CURSOR 3,1
  DISPLAY "                      LOOKING FOR WORKLIST"
  REM DISPLAY
15  REM CMD$="BASICA WORKLIST"
  REM WRITE CMD$ TO "TRANSFER.BAT"
  REM CLOSE "TRANSFER.BAT"
  REM DOS TRANSFER.BAT ! LOOK FOR WORKLISTS
  REM DOS CHKWLST ! LOOK FOR WORKLISTS
  READ WLST$ FROM "WLFILE"
  IF WLST$="NO WORKLISTS FOUND" THEN
20    WLFLAG=0 ! SET FLAG FOR NO WORKLISTS
    SPECFLAG=0
    DISPLAY
    DISPLAY "          ***** NO WORKLISTS FOUND *****"
    DISPLAY
  ELSE
    WLFLAG=1 ! SET FLAG FOR WORKLIST FOUND
    SPECFLAG=1 ! SET FLAG TO LOOK FOR SPEC FLAG
25  REM WRITE WLST$ TO "WLERASE.BAT" ! WRITE WORKLIST FILE NAME TO ERASE FILE
    REM READ WLST$ FROM "WLFILE" ! GET NAME OF WORKLIST FILE NAME TO RENAME
    REM WRITE WLST$ TO "WLERASE.BAT"
    REM CLOSE "WLERASE.BAT"
    REM BARCODE$=""
    REM WHILE BARCODE$() "END OF WORKLISTS" ! UNTIL END OF WORKLIST REACHED
30  REM READ BARCODE$ FROM "WORKLIST" ! READ BARCODE
    REM IF BARCODE$() "END OF WORKLISTS" !! IF NOT END OF WORKLIST
    REM CMD$="COPY F:" + BARCODE$ + ".SPE \LINK\SPEC" ! CMD TO COPY TO HOLD DIR
    REM WRITE CMD$ TO "TRANSFER.BAT" ! WRITE COMMAND TO TRANSFER FILE
    REM IF EOF("WORKLIST")=1 THEN ! IF EOF THEN
    REM BARCODE$="END OF WORKLISTS" ! SET TO EXIT LOOP
    REM END IF
35  REM END IF
    REM END WHILE ! UNTIL END OF WORKLIST REACHED
    REM CLOSE "TRANSFER.BAT"
    REM DOS TRANSFER ! EXECUTE TRANSFER OF SPEC FILES TO HOLDING DIRECTORY
    REM END IF
    REM CLOSE "WLFILE"
    REM END IF ! FIRST TIME THRU LOOP
40  REM END PROCEDURE

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PROCEDURE USEDCHK

! THIS PROCEDURE IS USED TO SEE IF A WORKLIST WAS ADJUSTED BEFORE IT WAS
 ! COMPLETED. IT READS THE ENTRIES IN THE WORKLIST AND COMPARES THEM TO A
 ! LIST OF USED CODES. WHEN AN UNUSED CODE IS FOUND, IT IS THE FIRST CODE TO
 ! BE TESTED, SKIPPING OVER THE CODES ALREADY USED. 2/21/50 WEA

10

IF RLCTRX=0 THEN ! IF FIRST TIME THRU LOOP

IX=0 ! SET COUNTER TO STAY IN LOOP

WHILE IX=0

READ BARCODE\$ FROM "WORKLIST" ! GET BARCODE FROM WORKLIST

READ USEDCODE\$ FROM "USEDLIST" ! GET USED BARCODE

15

IF BARCODE\$() "END OF WORKLISTS" THEN ! IF NOT END OF WORKLIST

IF BARCODE\$()USEDCODE\$ THEN ! IF CODE NOT USED YET

IX=1 ! SET FLAG TO EXIT LOOP

ELSE

RLCTRX=RLCTRX+1 ! INCREMENT USED CODE COUNTER

IF RLCTRX=1 THEN ! IF FIRST USED BARCODE FOUND

DISPLAY "USED BARCODES FOUND IN THIS WORKLIST: "

20

END IF

DISPLAY BARCODE\$! DISPLAY USED BARCODE

IF EOF("USEDLIST")=1 THEN ! IF END OF USED CODE LIST

IX=1 ! EXIT LOOP

END IF

END IF

ELSE ! IF END OF WORKLIST

IX=1 ! EXIT LOOP

25

END IF

END WHILE

CLOSE "USEDLIST"

IF RLCTRX=0 THEN ! IF NO USED CODES FOUND

CLOSE "WORKLIST" ! CLOSE FILE TO RESTART ON READ

ELSE

SET TIMER 1 FOR 2 SECONDS ! PAUSE FOR DISPLAY OF USED BARCODES

30

WAIT FOR TIMER 1

END IF

END IF ! FIRST TIME THROUGH LOOP

REM DISPLAY RLCTRX

REM DISPLAY BARCODE\$

REM DISPLAY USEDCODE\$

35

REM SET TIMER 1 FOR 2 SECONDS

REM WAIT FOR TIMER 1

END PROCEDURE

40

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PROCEDURE GET_DATA
  REM THIS PROCEDURE READS THE SPEC FILE DATA AND SAVES IT FOR USE IN TESTING
  REM SAMPLES. 5/15/90 WBA
  REM
  10 SPECDR$="\LINK\SPEC\" ! DIRECTORY LOCATION OF SPEC FILES
    F RLCTR%=0 THEN ! IF FIRST TIME THROUGH LOOP
      IF MODE$="REMOTE" THEN ! IF IN REMOTE MODE
        USEDCHK ! SEE IF ANY BARCODES ALREADY RUN IN THIS WORKLIST
      END IF
    END IF
    RLCTR%=RLCTR%+1 ! INCR REMOTE LOOP COUNTER
  15 READ BARCODE$ FROM "WORKLIST"
    SPFILENAME$=SPECDR$+BARCODE$+".SPE"
    IF BARCODE$() "END OF WORKLISTS" THEN
      CLEAR
      DISPLAY
      DISPLAY "          LOOKING FOR TEST SPECIFICATION FILE"
      DISPLAY
      SPECFLAG=1 ! SET FLAG FOR BARCODE FOUND
      20 CMD$="COPY "+SPECDR$+SPFILENAME$+" \PERL"
      REM WRITE CMD$ TO "TRANSFER.BAT"
      REM CLOSE "TRANSFER.BAT"
      REM DOS TRANSFER.BAT ! COPY BARCODE TEST DATA TO PERL
      CTR%=0
      RODCHECK%=1 ! SET FLAG TO COMPARE ACTUAL ROD LENGTH TO EXPECTED
      RLFLAG=0
      25 CRFLAG=0
      CFLAG=0
      DFLAG=0
      FLFLAG=0 ! REINIT FLAGS
      FRFLAG=0
      SAMNO%=0
      CIGLEN%=0
      30 FILLEN%=0
      TST1%=0
      TST2%=0
      TST3%=0
      TST4%=0
      TST5%=0
      TST6%=0
      35 T1%=0
      T2%=0
      T3%=0
      T4%=0
      T5%=0
      T6%=0
      FOR IX=1 TO 25
        READ D$ FROM SPFILENAME$
        IF EOF (SPFILENAME$)=1 THEN
          IX=25 ! SET FOR IX CNTR TO 25 IF END OF FILE
        END IF
        AX=LEN(D$) ! SET A = TO LENGTH OF STRING
        Z$="" ! SET Z$ = TO CHAR TO LOOK FOR
        Z1$=INSTR(D$,Z$) ! FIND POS OF SPACE
        BX=VAL(Z1$) ! SET B = TO VAL OF POS OF SPACE
        45 T$=LEFT$(D$,BX) ! GET DATA DESCRIPTOR STRING
        DISPLAY "DATA STRING = ";
        display d$
        REM DISPLAY "T$ = ";T$;
        IF BX=0 THEN ! IF SPACE NOT FOUND IN STRING
          DISPLAY D$
          DISPLAY "SPEC FILE ERROR"
          50 INPUT "WHAT IS PROPER DATA",D$
        ELSE
          D$=RIGHT$(D$,A-Z1$) ! GET REMAINDER OF STRING

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REM      DISPLAY "D$ = ";D$
      CASE T$
        IS "BC " : ! CODE
          BCODE$=D$
        REM      IS "LENGTH " : ! CIGARETTE LENGTH
        10      IS "CLENGTH " :
          CIGLEN%=VAL(D$)
        REM      IS "TIPP_LEN " : ! TIPPING LENGTH
        IS "FLENGTH " :
          FILLEN%=VAL(D$)
        IS "TEST " : ! TEST SPECIFICATION
          AX=LEN(D$) ! SET A = TO LENGTH OF STRING
          Z1%=INSTR(D$,Z$) ! FIND POS OF = SIGN
          B%=VAL(Z1$) ! SET B = TO VAL OF POS OF SPACE
          T$=RIGHT$(D$,AX-B%) ! GET NUMBER OF TEST TO BE RUN
          IF B%>1 THEN
            D$=LEFT$(D$,B%-1) ! GET NAME OF TEST
          END IF
          CASE D$
            IS "CIG_LEN" :
              RLFLAG=1 ! SET ROD LENGTH FLAG
              TST1% = VAL(T$)
              WRITE D$ TO "CL.DAT" ! WRITE TEST NAME TO DATA FILE
              CLOSE "CL.DAT"
            REM      END IF
            IS "TOT_RTD" :
              CRFLAG=1 ! SET TOT RTD FLAG
              TST2% = VAL(T$)
              WRITE D$ TO "CRTD.DAT" ! WRITE TEST NAME TO DATA FILE
              CLOSE "CRTD.DAT"
            REM      END IF
            IS "CIRC" :
              CFLAG=1 ! SET CIRCUMFERENCE FLAG
              TST3% = VAL(T$)
              WRITE D$ TO "CD.DAT" ! WRITE TEST NAME TO DATA FILE
              CLOSE "CD.DAT"
            REM      END IF
            IS "VENT_PER" :
              DFLAG=1 ! SET DILUTION FLAG
              TST4% = VAL(T$)
              WRITE D$ TO "DIL.DAT" ! WRITE TEST NAME TO DATA FILE
              CLOSE "DIL.DAT"
            35      REM      END IF
            IS "FLT_LEN" :
              FLFLAG=1 ! SET FILTER LENGTH FLAG
              TST5% = VAL(T$)
              WRITE D$ TO "FL.DAT" ! WRITE TEST NAME TO DATA FILE
              CLOSE "FL.DAT"
            40      REM      END IF
            IS "FLT_RTD" :
              FRFLAG=1 ! SET FILTER RTD FLAG
              TST6% = VAL(T$)
              WRITE D$ TO "FRTD.DAT" ! WRITE NAME TO TEST DATA FILE
              CLOSE "FRTD.DAT"
            REM      END IF
            DEFAULT:
              45      DISPLAY "TEST SPEC ERROR"
            END CASE
            IF VAL(T$)>SAMNO% THEN ! IF # SAMPLES FOR THIS TEST > TOTAL #
              SAMNO%=VAL(T$) ! SAVE AS NEW TOTAL #
            END IF
            DEFAULT:
              50      DISPLAY "SPEC FILE ERROR"
            END CASE
          END IF
        NEXT I$

```

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5

```

CLOSE SPFILENAME$
CMD$="COPY "+SPFILENAME$+" "+SPECDR$+BARCODE$+".TPE"
APPEND CMD$ TO "WLERASE.BAT" ! ADD SPECFILE NAME TO RENAME LIST
CMD$="DEL "+SPFILENAME$ ! DELETE SPEC FILE
10 APPEND CMD$ TO "WLERASE.BAT"
CLOSE "WLERASE.BAT"
IF SAMNOX=0 THEN ! IF NO TESTS FOUND IN LIST
    DISPLAY
    DISPLAY " NO TESTS WERE REQUESTED FOR THIS SAMPLE"
    DISPLAY
    ERRRESP
END IF
15 WHILE (CIGLENX<77) OR (CIGLENX>120) ! GET CIGARETTE LENGTH ENTRY
    DISPLAY
    DISPLAY " *** NO CIGARETTE LENGTH FOUND IN SPEC FILE ***"
    ALARM_ON
    SET TIMER 1 FOR 1 SECOND
    WAIT FOR TIMER 1
    ALARM_OFF
20 MSG$="      ENTER CIGARETTE LENGTH (MM) "
    GETKEY ! GET OPERATOR RESPONSE
    CIGLENX=VAL(IN$) ! CONVERT RESPONSE TO NUMERIC
END WHILE
WHILE (FILLLENX<18) OR (FILLLENX>36) ! GET FILTER LEN ENTRY
    DISPLAY
    DISPLAY " *** NO FILTER LENGTH FOUND IN SPEC FILE ***"
25 ALARM_ON
    SET TIMER 1 FOR 1 SECOND
    WAIT FOR TIMER 1
    ALARM_OFF
    MSG$="      ENTER FILTER LENGTH (MM) "
    GETKEY ! GET OPERATOR RESPONSE
    FILLLENX=VAL(IN$) ! CONVERT TO NUMERIC
30 END WHILE
ELSE ! IF BARCODE NOT FOUND
    SPECFLAG=0 ! RESET BARCODE FLAG
    CLOSE "WORKLIST"
    DISPLAY
    DISPLAY "      ***** NO MORE BARCODES FOUND IN THIS LIST *****"
    DISPLAY "      ***** ERASING TEST SPECIFICATION FILES *****"
35 DISPLAY
    CMD$="NO WORKLISTS FOUND"
    WRITE CMD$ TO "WLFILE" ! SET FLAG FOR WORKLIST FINISHED
    CLOSE "WLFILE"
    DOS WLERASE ! ERASE WORKLIST AND SPEC FILES
END IF ! IF BARCODE FOUND
REM END IF ! IF WORKLIST FOUND
40 END PROCEDURE

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```

PROCEDURE GETKEY
! THIS PROCEDURE ALLOWS ENTRY OF DATA FROM KEYBOARD CHARACTER AT A TIME.
! 1/29/90 WBA

```

10

```

KEY$="A"

```

```

WHILE ASC(KEY$) < 13 ! UNTIL CARRIAGE RETURN INPUT

```

```

  IN$=""

```

```

  DISPLAY MSG$;

```

```

  NUMERIC%=1 ! SET FLAG TO GET NUMERIC DATA

```

```

  WHILE (NUMERIC%=1) AND (ASC(KEY$) < 13) ! WHILE NUMERIC DATA INPUT

```

```

    KEY$ = INKEY$ ! GET KEY

```

15

```

    IF ASC(KEY$) < 13 THEN ! IF NOT CARRIAGE RETURN

```

```

      DISPLAY KEY$; ! ECHO CHARACTER

```

```

      IF (ASC(KEY$) > 47) AND (ASC(KEY$) < 58) THEN ! IF NUMERIC CHARACTER

```

```

        IN$=IN$+KEY$ ! FORM STRING

```

```

      ELSE

```

```

        KEY$="A"

```

```

        NUMERIC%=0 ! SET FLAG FOR NON-NUMERIC DATA

```

20

```

        DISPLAY

```

```

        DISPLAY

```

```

        DISPLAY " *** NUMERIC DATA REQUIRED ***"

```

```

        DISPLAY

```

```

      END IF

```

```

    END IF

```

```

  END WHILE

```

25

```

END WHILE

```

```

REM DISPLAY " IN$ = "; IN$

```

```

REM SET TIMER 1 FOR 2 SECONDS

```

```

REM WAIT FOR TIMER 1

```

```

END PROCEDURE

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```

PROCEDURE LOGPROB
  D$=DATE$+" "+TIME$+" " GET DATE AND TIME
  D$=D$+"CIGARETTE #"+STR$(DLINEX+1)+" " ! ADD SAMPLE NUMBER
  PROB$=D$+PROB$ ! ADD PROBLEM MESSAGE TO STRING
10  IF PROBCTR=0 THEN ! IF NO ENTRY LOGGED YET
    WRITE PROB$ TO "TROUBLE.DAT"
  ELSE
    APPEND PROB$ TO "TROUBLE.DAT"
  END IF
  CLOSE "TROUBLE.DAT"
  PROBCTR=PROBCTR+1 ! INCREMENT PROBLEM COUNTER
15 END PROCEDURE

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A23

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```

PROCEDURE FILLHOPR
! THIS PROCEDURE MOVES GARETTE FROM THE MAIN ROTATING HOPPER TO THE FEED
! HOPPER

```

```

10  S9=IN9 ! READ INPUT
    WHILE S9 = 0 ! DO NOTHING IF HOPPER BUSY
      DISPLAY "WAITING FOR HOPPER TO FINISH"
      S9=IN9
    END WHILE
    IF S9 = 1 THEN
      SW6_ON ! TURN ON HOPPER
15  WHILE S9=1 ! WAIT FOR HOPPER TO CO ACTIVE
        S9=IN9
      END WHILE
      SW6_OFF ! TURN HOPPER OFF
      REM HOP4 ! MOVE ROBOT INTO POSITION
      WHILE S9=0 ! WAIT FOR HOPPER TO FINISH
        S9=IN9
20  END WHILE
        FEEDSAMP ! PRIME SAMPLE FEEDER
      END IF
    END PROCEDURE

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A24

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```

PROCEDURE FEEDSAMP
REM  DISPLAY "FEEDSAMP"
FEEDCHK ! WAIT UNTIL FEEDER IS NOT BUSY
S3=IN8 ! READ FEEDER STATUS
10  IF S8 = 1 THEN
    SW7_ON      ! TURN ON FEEDER
    SET TIMER 1 FOR 2 SECONDS ! WAIT FOR FEEDER TO GO ACTIVE
    WAIT FOR TIMER 1
    SW7_OFF     ! TURN FEEDER OFF
    END IF
REM  DISPLAY "END FEEDSAMP"
15  END PROCEDURE

```

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```
PROCEDURE FEEDCHK
  S8=IN8 ! READ INPUT
  SW7_OFF ! TURN OFF FEEDER
  REM DISPLAY "FEEDCHK ";
10  IF S8=0 THEN
    DISPLAY
    DISPLAY "WAITING FOR FEEDER TO FINISH"
    END IF
    WHILE S8 = 0 ! DO NOTHING IF FEEDER BUSY
      S8=IN8
    REM DISPLAY S8;
    SET TIMER 1 FOR 1 SECOND
15  WAIT FOR TIMER 1
    END WHILE
  END PROCEDURE
```

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PROCEDURE DISHEADR

```

CLEAR
NUMSAMP%=6 ! SET LINE TO DISPLAY # OF SAMPLES
DISPLAY DATE$,TIME$
10  *EN  DISPLAY
    DISPLAY "BARCODE = ";BCODE$
    DISPLAY "SAMPLE SIZE = ";SAMNO%;
    DISPLAY "CIGARETTE LENGTH = ";CIGLEN%, " FILTER LENGTH = ";FLEN%
    DISPLAY
    DISPLAY "      CIG LEN      TOT RTD      VENT      CIRC      FIL LEN      FLT RTD"
15  CURSOR NUMSAMP%,6
    DISPLAY "("+TST1%+""); ! DISPLAY # CIG LEN SAMPLES
    CURSOR NUMSAMP%,17
    DISPLAY "("+TST2%+""); ! # CRTD SAMPLES
    CURSOR NUMSAMP%,27
    DISPLAY "("+TST4%+""); ! # VENT SAMPLES
    CURSOR NUMSAMP%,35
    DISPLAY "("+TST3%+""); ! # CIRC SAMPLES
20  CURSOR NUMSAMP%,44
    DISPLAY "("+TST5%+""); ! # FLEN SAMPLES
    CURSOR NUMSAMP%,55
    DISPLAY "("+TST6%+""); ! # FRTD SAMPLES
    REM SET TIMER 1 FOR 9 SECONDS
    REM WAIT FOR TIMER 1
    END PROCEDURE
25

```

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A27

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```

PROCEDURE GSAMPLE
! THIS PROCEDURE FEEDS SAMPLE FROM THE FEED HOPPER TO THE ROBOT PICKUP
! PT. THE LENGTH CAMERA IS USED TO DETECT THE PRESENCE OF THE SAMPLE, AND
! IF REQUIRED, THE LENGTH IS READ AND RECORDED. IF THE SAMPLE IS NOT
! DETECTED, THE SYSTEM WILL ATTEMPT 2 OTHER FEEDS BEFORE INDICATING A
10 ! PROBLEM AND HALTING OPERATION. THE OPERATOR CAN THEN MAKE REPAIRS, OR
! ABORT THE SYSTEM OPERATION
!
SPEED 9
OPEN
TRY_CTR:=0
FAULT$=""
15 REM PRINT "FEEDIN SAMPLE ";TIME$ ! *****
GETLEN ! SEE IF SAMPLE ALREADY THERE ***** REMOVE AFTER TESTING
IF VAL(CLEND$) < 77 THEN ! IF SAMPLE NOT THERE
FEEDSAMP ! FEED SAMPLE OUT OF HOPPER
END IF
REM HOP4
CONTINUOUS
20 HOP2
HOP3
END CONTINUOUS
WHILE VAL(CLEND$) < 77
GETLEN ! SEE IF SAMPLE PRESENT *****
IF VAL(CLEND$) < 77 THEN ! IF SAMPLE NOT PRESENT
TRY_CTR:=TRY_CTR+1
25 IF TRY_CTR < 3 THEN ! IF NOT THIRD ATTEMPT
ALARM_ON ! SOUND ALARM
SET TIMER 1 FOR 1 SECONDS
WAIT FOR TIMER 1
ALARM_OFF
FEEDSAMP ! TRY AGAIN TO FEED SAMPLE
SET TIMER 1 FOR 2 SECONDS
30 WAIT FOR TIMER 1
ELSE
FEEDCHK ! WAIT FOR FEEDER TO STOP
DISPLAY
DISPLAY "*****"
DISPLAY "SAMPLE DID NOT FEED"
DISPLAY "CHECK FEED OPERATION"
35 DISPLAY "CHECK FOR SAMPLES IN FEED HOPPER"
SET TIMER 1 FOR 1 SECONDS
WAIT FOR TIMER 1
ERRRESP ! GET OPERATOR'S INSTRUCTIONS FOR WHAT TO DO NEXT
IF FAULT$="C" THEN ! IF TO CONTINUE WITH THIS BARCODE
TRY_CTR:=0 ! RESET COUNTER
FEEDSAMP ! FEED AGAIN
40 END IF
IF FAULT$="" THEN ! IF NOT TO CONTINUE
CLEND$="80" ! SET TO EXIT LOOP
END IF
END IF
END IF
END WHILE
45 IF FAULT$="S" THEN ! IF SKIPPING THIS CIGARETTE PICKUP
PROB$="CIGARETTE DID NOT FEED; SAMPLE ABORTED BY ROBOT" ! TROUBLE MESSAGE
LOGPROB ! LOG THE PROBLEM IN THE TROUBLE FILE
FAULT$="F" ! SET TO NOT ATTEMPT PICK UP
SAMCTX=1 ! RESET VARIABLES TO ABORT THE REST OF THIS SAMPLE
TST1X=0
TST2X=0
TST3X=0
50 TST4X=0
TST5X=0
TST6X=0

```

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5

```

      END IF
      IF FAULT$(">"F" THEN ! IF NOT GOING TO NEXT BARCODE
      IF FAULT$(">"A" THEN ! NOT ABORTING RUN
      REM PRINT "PICKING UP SAMPLE ";TIME$ ! *****
      RLEN ! GET AND SAVE LENGTH DATA *****
10      HOP1 ! MOVE TO PICKUP PT
      CLOSE
      SIH%=1 ! SET FLAG FOR SAMPLE IN HAND
      END IF
      END IF
      HOP3
      HOP4
15      REM PRINT " PICKUP COMPLETED ";TIME$ ! *****
      END PROCEDURE

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```

PROCEDURE ERRRESP
! THIS PROCEDURE GETS OPERATOR'S INSTRUCTIONS ON WHAT THE ROBOT SHOULD
! DO FOLLOWING DETECTION OF AN ERROR. THE CHOICES ARE:
! "F" - TO ABORT TESTING OF THE CURRENT BARCODE AND START WITH THE NEXT
! "A" - TO ABORT TESTING OF THE CURRENT BARCODE AND ALL REMAINING BARCODES
10 ! "C" - COMPLETE TESTING OF THE CURRENT BARCODE
!
ALARM_ON ! INDICATE OCCURRENCE OF ERROR CONDITION
SET TIMER 1 FOR 1 SECONDS
WAIT FOR TIMER 1
ALARM_OFF
15 IF ERRSTOP$="T" THEN ! IF STOPPING ON DETECTED ERRORS
    FAULT$=""
ELSE
    FAULT$="S" ! SET FAULT RESPONSE TO SKIP CURRENT OPERATION
END IF
WHILE FAULT$=""
    DISPLAY
    20 DISPLAY "ENTER C TO CONTINUE TESTING OF THE CURRENT BARCODE,"
    DISPLAY "      F TO STOP TESTING OF THIS BARCODE AND START WITH THE NEXT,"
    DISPLAY "      A TO ABORT TESTING OF THIS AND ALL REMAINING BARCODES"
    DISPLAY
    INPUT "WHAT SHOULD I DO"; FAULT$
    DISPLAY
    CASE FAULT$
    25 IS "C":
        DISPLAY "CONTINUING TESTING"
        REM FEEDSAMP ! FEED AGAIN
    IS "F":
        DISPLAY "ABORTING THIS BARCODE AND GOING TO THE NEXT"
        PROB$=" SAMPLE ABORTED BY OPERATOR" ! CREATE TROUBLE MESSAGE
        LOGPROB ! LOG IN TROUBLE FILE
        SAMCTX=1 ! SET FLAGS AND COUNTERS TO ABORT THIS BARCODE
    30 TST1X=0
        TST2X=0
        TST3X=0
        TST4X=0
        TST5X=0
        TST6X=0
    IS "A":
    35 DISPLAY "ABORTING THIS BARCODE AND ALL REMAINING BARCODES"
        PROB$=" RUN ABORTED BY OPERATOR" ! CREATE TROUBLE MESSAGE
        LOGPROB ! SAVE IN TROUBLE FILE
        SAMCTX=1
        TST1X=0
        TST2X=0
        TST3X=0
        TST4X=0
        TST5X=0
        TST6X=0
        SIHX=0
        40 DEFAULT:
            FAULT$="" ! RESET TO STAY IN LOOP
        END CASE
    45 END WHILE
END PROCEDURE

```

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A30

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```

PROCEDURE GETLEN
! THIS PROCEDURE READS THE ROD LENGTH CAMERA AND CONVERTS THE READING TO A
! LENGTH VALUE. THE # OF PIXELS TO THE BEST LEFT DARK EDGE IS RECEIVED FROM
! FROM THE CAMERA, WITH 239.99 REPRESENTING THE RIGHTMOST EDGE OF THE FIELD-
10 ! OF-VIEW, AND 0 REPRESENTING THE LEFTMOST. THIS VALUE IS CONVERTED TO MM,
! WITH 50 MM BEING THE MAXIMUM FIELD OF VIEW. THE VALUE CALCULATED IS ADDED
! TO THE OFFSET OF 75 MM, AND IS ROUNDED BY .005 MM, TO GET THE NEAREST
! HUNDRETH MM.
!
  DEFINE CL$ AS CLEN
  CL$="XMZ" ! SEND 'WAKE UP' MESSAGE
15 REM CURSOR 22,40
  REM DISPLAY CL$;
  SEND CL$
  RECEIVE CL$
  REM DISPLAY " ";CL$;
  REM CL$="XTL9" ! MESS TO SEND RIGHTMOST LEFT DARK EDGE
  CL$="XTL0" ! MESS TO SEND BEST LEFT DARK EDGE
20 REM CL$="XTWB00" ! GET BRIGHT WIDTH
  REM DISPLAY " ";CL$;
  SEND CL$
  RECEIVE CL$
  REM DISPLAY " ";CL$;
  CL$="T" ! SEND MESS TO TRANSMIT DATA TO GAUGE
  REM DISPLAY " ";CL$;
25 SEND CL$
  RECEIVE CL$ ! RECIEVE CIG LENGTH DATA
  REM DISPLAY " ";CL$
  REM DISPLAY "CL$ = ";CL$
  CLEND$=RIGHT$(CL$,6) ! GET RID OF UNWANTED CHARS
  RL=239.99-(VAL(CLEND$)) ! CONVERT TO VALUE: 239.99=RIGHTMOST, 0=LEFTMOST
  RL=((RL*50)/239.99)+75.005 ! DO MATH TO CONVERT CIG LEN DATA
30 REM DISPLAY RL;
  REM RL=VAL(CLEND$) ! USE THIS CONVERSION WHEN READING WIDTH
  REM RL=((RL*50)/239.99)
  REM DISPLAY "RL = ";RL
  CLEND$=STR$(RL)
  REM DISPLAY "CLEND$ = ";CLEND$
  DECP$=""
35 DELOC$=INSTR(CLEND$,DECP$) ! FIND DECIMAL PT
  CLEND$=VAL(DECLOC$) ! CONVERT POSITION OF DEC PT
  IF CLEND$>0 THEN ! IF DEC PT FOUND
    CLEND$=MID$(CLEND$,2,CLEND$+1) ! STRIP OFF CHARS BEYOND 2ND DEC PLACE
  ELSE
    CLEND$=CLEND$+".00" ! ADD 2 DEC PLACES
  END IF
  MAN1$="LENGTH = "+CLEND$
40 DISMANUL ! DISPLAY LENGTH ON MANUAL CONTROL DISPLAY
  REM DISPLAY "CLEND$ = ";CLEND$
  REM SET TIMER 1 FOR 1 SECOND
  REM WAIT FOR TIMER 1
  END PROCEDURE

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A31

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```

PROCEDURE DISMANUL
! THIS PROCEDURE DISPLAYS THE MESSAGE MAN1$ ON THE MANUAL CONTROL STATION
! DISPLAY.

```

10

```

DEFINE MAN$ AS MANUAL
REN ESC$="\33" ! ESC CHARACTER
REM TERM$="\02" ! TERMINATOR = STX
REM M$="m" ! COMMAND TO PROGRAM FUNCTION KEY

```

15

```

CLR$=""
MAN$=CLR$
SEND MAN$ ! CLEAR PREVIOUS DISPLAY
MAN$=MAN1$
SEND MAN$
REM SET TIMER 1 FOR 2 SECONDS
REM WAIT FOR TIMER 1
END PROCEDURE

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A32

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```

PROCEDURE RLEN
  REM THIS PROCEDURE RECORDS ROD LENGTH. IT ALSO COMPARES THE LENGTH OF THE
  REM FIRST CIGARETTE IN THE SAMPLE TO THE EXPECTED LENGTH. IF NOT WITHIN
  REM RANGE OF THE EXPECTED LENGTH, AN ERROR IS INDICATED. 5/15/90 WBA
10  REM PRINT "MEASURING ROD LENGTH";TIME$ ! *****
  DEFINE CL$ AS CLEN
  REM GETLEN ! READ CAMERA AND GET LENGTH
  REM CLENDLEN=LEN(CLEND$)
  REM CLEND$=LEFT$(CLEND$,CLENDLEN-1) ! STRIP OFF UNWANTED DIGIT
  REM DISPLAY CLEND$
  REM PRINT " MEASURING ROD LEN COMPLETED "; TIME$ ! *****
  IF VAL(CLEND$) < 124 THEN ! IF SAMPLE PRESENT
15  REM PRINT "CHECKING FOR LEN ERROR ";TIME$ ! *****
    IF (RODCHECK%=1) AND (ABS(VAL(CLEND$)-CIGLEN%) > 3) THEN
      ! IF DIFFERENCE BETWEEN ACTUAL AND EXPECTED LENGTHS > 3 MM
      RODCHECK%=0 ! CLEAR ROD CHECK FLAG
      DISPLAY
      DISPLAY "MEASURED ROD LENGTH IS NOT WHAT WAS EXPECTED"
      DISPLAY "  ACTUAL ROD LENGTH = ";CLEND$
20  DISPLAY "  EXPECTED ROD LENGTH = ";CIGLEN%
      IF ERRSTOP="T" THEN ! IF STOPPING ON DETECTED ERRORS
        ERRRESP ! GET OPERATOR INSTRUCTIONS FOR WHAT TO DO
      ELSE
        CIGLEN%=STR$(CIGLEN%) ! CONVERT EXPECTED LENGTH TO STRING
        PROB$="ROD LENGTH="+CLEND$+" ; EXPECTED LENGTH="+CIGLEN% ! TROUBL MESS
        LOGPROB ! LOG IN PROBLEM FILE
25  END IF
    END IF
    RODCHECK%=0 ! RESET ROD CHECK FLAG
    REM PRINT " LEN ERROR CHECK COMPLETED ";TIME$ ! *****
    IF (RLFLAG = 1) AND (TST1%<0) THEN ! IF ROD LENGTH REQUIRED
      REM PRINT "DISPLAYING AND SAVING ROD LEN DATA ";TIME$ ! *****
      REM CURSOR (T1%*17)+7,6 ! POSITION CURSOR
      CURSOR (DLINEX*17)+7,6
30  DISPLAY CLEND$; ! DISPLAY DATA
      T1%=T1%+1 ! INCR LOOP CNTR
      REM IF T1% = 1 THEN
      REM WRITE CLEND$ TO "CL.DAT" ! PUT DATA IN FILE
      REM ELSE
        APPEND CLEND$ TO "CL.DAT" ! PUT DATA IN FILE
35  REM END IF
      CLOSE "CL.DAT"
      TST1% = TST1%-1 ! DEC # OF TEST CTR
      REM PRINT " SAVING ROD LEN DATA COMPLETED ";TIME$ ! *****
    END IF
  END IF
END PROCEDURE

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A33

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PROCEDURE CRTDCHK
  ! THIS PROCEDURE IS TO CHECK THE TOTAL RTD INSTRUMENT BEFORE ATTEMPTING TO
  ! INSERT A SAMPLE INTO IT. IT READS THE METER AND ATTEMPTS TO BLOW OBJECT
  ! OUT IF IT FEELS THAT SOMETHING IS ALREADY IN THE INSTRUMENT. IT READS THE
  ! METER AGAIN AND INDICATES AN ERROR TO THE OPERATOR IF IT FEELS THAT
  ! SOMETHING IS STILL IN THE INSTRUMENT. 4/26/90 WSA
10  REM PRINT "CHECKING IF CRTD INSTR EMPTY "; TIMES ! ****
    SW2_ON
    READCRTD ! READ CIGARETTE RTD
    REM READVENT
    SW2_OFF
15  IF (VAL(CR$)>5) THEN ! OR (VAL(D$)>5) THEN ! IF INSTRUMENT NOT EMPTY
    SW3_ON ! ATTEMPT TO BLOW OBJECT OUT
    SET TIMER 1 FOR 2 SECONDS
    WAIT FOR TIMER 1
    SW3_OFF
    FAULT$=""
    REPEAT$="T"
20  WHILE REPEAT$ = "T" ! CHECK UNTIL NO REPEAT REQUIRED
    SW2_ON
    READCRTD ! TRY AGAIN
    REM READVENT
    SW2_OFF
    IF (VAL(CR$)>5) THEN ! OR (VAL(D$)>5) THEN ! IF INSTRUMENT STILL NOT
    DISPLAY
25  DISPLAY "THERE APPEARS TO BE SOMETHING ALREADY IN THE CIGARETTE RTD ";
    DISPLAY "INSTRUMENT."
    DISPLAY "PLEASE CHECK IT."
    ERRRESP ! GET OPERATOR'S INSTRUCTION
    IF ERRSTOP$="F" THEN ! IF NOT STOPPING ON DETECTED ERRORS
    PROB$="CRTD NOT EMPTY" ! SET TROUBLE MESSAGE
    LOGPROB ! SAVE TROUBLE IN FILE FOR WORKSTATION
    REPEAT$="F" ! SET TO EXIT LOOP
30  END IF
    ELSE
    REPEAT$="F" ! SET TO EXIT LOOP
    END IF
    END WHILE
    END IF
35  REM PRINT " CRTD INSTR CHECK COMPL "; TIMES ! ****
    END PROCEDURE

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A34

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```

PROCEDURE TOTRTD
  ! THIS PROCEDURE READS CRITICAL RTD AND VENTILATION IF REQUIRED, AND DISPLAYS
  ! THE DATA. 1/19/90

```

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```

  REM CRFLAG=1 ! **** REMOVE AFTER DEBUG
  REM TST2%=1 ! ****
  REM DFLAG=1 ! ****
  REM TST4%=1 ! ****

```

```

  SPEED 6
  CRTDLOAD

```

15

```

  IF (CRFLAG=1) AND (TST2%>0) THEN ! IF CRTD TEST REQUIRED
    READCRTD ! GET CRTD DATA
    CURSOR (DLINEX@17)+7,18
    DISPLAY CR%;
    T2%=T2%+1 ! INCR LOOP CNTR
    TST2%=TST2%-1 ! DECR CIG RTD TEST CTR
    APPEND CR% TO "CRTD.DAT" ! SAVE CIG RTD DATA
    CLOSE "CRTD.DAT"

```

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```

  REM PRINT " SAVE COMPLETED ";TIME$ ! *****
  END IF
  IF (DFLAG=1) AND (TST4%>0) THEN ! IF DILUTION REQUIRED
    READVENT ! READ VENT DATA
    CURSOR (DLINEX@17)+7,28
    DISPLAY D%;
    T4%=T4%+1 ! INCR LOOP CNTR
    TST4%=TST4%-1 ! DEC DIL TEST CTR
    APPEND D% TO "DIL.DAT" ! SAVE DIL DATA
    CLOSE "DIL.DAT"

```

25

```

  REM PRINT " SAVE COMPLETED ";TIME$ ! *****
  END IF
  CLOSE

```

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```

  SW2_OFF ! DATA TAKEN.TURN OFF VALVE
  SPEED 6
  CRTDUNLD ! UNLOAD INSTRUMENT
  END PROCEDURE

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PROCEDURE CRTDLOAD

REM SPEED 6

SPEED 9

CRTD3

10

CONTINUOUS

CRTD5

CRTD2

CRTD1

END CONTINUOUS

SW2_ON ! TURN ON VALVE TO TAKE RTD DATA

REM SET TIMER 1 FOR 1 SECOND

15

REM WAIT FOR TIMER 1

OPEN

END PROCEDURE

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AB6

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```

PROCEDURE READCRTD
! THIS PROCEDURE READS THE CRTD METER DATA. IT SENDS THE 'XS' MESSAGE TO
! SEND DATA. THE PROGRAM WAITS IN A LOOP UNTIL THE DIFFERENCE BETWEEN 2
! CONSECUTIVE READINGS IS LESS THAN 2. IT THEN SAVES THE LAST READING AS
10 ! THE DATA. THE DATA IS FORMATED FOR FUTURE USE. 2/5/50 WEA
    DEFINE CR$ AS CPDI
    DEFINE CRT$ AS CPDI
    REM SET TIMER 1 FOR .5 SECONDS
    REM WAIT FOR TIMER 1
    DIFF=20 ! PRESET THE DIFFERENCE IN READINGS
    CRL=0
15    WHILE DIFF > 1 ! WAIT UNTIL DIFF IN READINGS < 1
        GETCRTD
    END WHILE
    CR$=STR$(C) ! CONVERT BACK TO STRING
    CRTDD$=CR$
    REM DISPLAY CR$
    REM SET TIMER 1 FOR 2 SECONDS
20    REM WAIT FOR TIMER 1
    END PROCEDURE

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A37

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PROCEDURE GETCRTD
! THIS PROCEDURE READS ONE CRTD METER DATA. IT SENDS THE 'XS' MESSAGE TO
! SEND DATA. THE DATA IS FORMATTED FOR FUTURE USE.
  DEFINE CR$ AS CPDI
  DEFINE CRT$ AS CPDI
10  CRT$="XS"
  SEND CRT$ ! SEND CODE TO TX CIG RTD DATA
  RECEIVE CR$ ! GET DATA
  REM DISPLAY CR$;
  CR$=MID$(CR$,2,6) ! GET RID OF UNWANTED CHARS
  C=VAL(CR$) ! STRIP OFF LEADING ZEROS
  REM DISPLAY C;
15  DIFF=ABS(C-CRL) ! GET ABSOLUTE DIFF BET NEW AND LAST READINGS
  CRL=C ! SAVE LAST READING
  CR$=STR$(C) ! CONVERT BACK TO STRING
  CRTDD$=CR$
  REM DISPLAY CR$
  REM SET TIMER 1 FOR 2 SECONDS
  REM WAIT FOR TIMER 1
20  END PROCEDURE

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A38

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PROCEDURE READVENT

! THIS PROCEDURE READS ONE VENTILATION (DILUTION) METER DATA. IT SENDS THE
 ! 'XS' MESSAGE TO SEND DATA. THE PROGRAM WAITS IN A LOOP UNTIL THE
 ! DIFFERENCE BETWEEN 2 CONSECUTIVE READINGS IS LESS THAN 2. IT THEN SAVES
 ! THE LAST READING AS THE DATA, WHICH IS FORMATTED FOR FUTURE USE.

10

DEFINE D\$ AS DIL ! RECEIVE BUFFER FOR DIL METER
 DEFINE DT\$ AS DIL ! TRANSMIT BUFFER
 REM SET TIMER 1 FOR .5 SECONDS
 REM WAIT FOR TIMER 1

15

DT\$="XS" ! SEND CODE TO TX DIL DATA
 DIFF=20 ! PRESET THE DIFFERENCE IN READINGS
 CRL=0 ! CLEAR LAST READING
 WHILE DIFF > 2 ! WAIT UNTIL DIFF IN READINGS < 2

20

SEND DT\$
 RECEIVE D\$! GET DIL DATA
 D\$=MID\$(D\$,2,6) ! STRIP OFF UNWANTED CHARS
 C=VAL(D\$) ! STRIP OFF LEADING ZEROS
 DIFF=ABS(C-CRL) ! GET ABSOLUTE DIFF BET NEW AND LAST READINGS
 CRL=C

END WHILE
 D\$=STR\$(C) ! CONVERT BACK TO STRING
 DILD\$=D\$
 REM DISPLAY D\$;
 END PROCEDURE

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PROCEDURE CRTDUNLD
 CLOSE
 SW2 OFF ! DATA TAKEN TURN OFF VALVE
 SPEED 6
 CONTINUOUS
 CRTD2
 CRTD3
 END CONTINUOUS
 END PROCEDURE

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A40

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PROCEDURE CIR
  DEFINE C$ AS CIRC
  CIRLOAD ! PUT SAMPLE IN LASERMIKE
  CIRCHK ! SEE IF SAMPLE IN LASERMIKE
10  IF SIH%=1 THEN ! IF SAMPLE PRESENT
    C$="300"
    SEND C$ ! SEND MESS TO RESET GAUGE
    RECEIVE C$
    C$="303"
    SEND C$ ! RUN LASERMIKE
    RECEIVE C$
15  IF CIGLEN% > 85 THEN
    OPEN ! IF CIG > 85, MOVE WHILE READING
    C1
  ELSE
    SET TIMER 1 FOR 1 SECOND
    WAIT FOR TIMER 1
  END IF
20  C=10 ! PRESET CIRCUMFERENCE
  WHILE (C < 12) OR (C > 30) ! WAIT UNTIL CIRCUMFERENCE READ
    C$="201"
    SEND C$ ! SEND MESS TO SEND MEASUREMENT
    RECEIVE C$ ! GET DATA FROM GAUGE
    C$=RIGHT$(C$,5) ! GET RID OF UN WANTED CHARS
    C=VAL(C$) ! CONVERT FROM STRING TO NUMERIC VALUE
25  REM C=VAL(C$)+.05 ! ROUND VALUE
  END WHILE
  REM C$=STR$(C) ! CONVERT BACK TO STRING
  REM DECP$=""
  REM DECCLOC$=INSTR(C$,DECP$) ! FIND DEC PT
  REM CX=VAL(DECCLOC$)
  REM IF CX<>0 THEN ! IF DEC PT FOUND
30  REM C$=MID$(C$,1,CX+1) ! SAVE TO NEAREST .1 MM
  REM ELSE ! IF DEC PT NOT FOUND
  REM C$=C$+".0" ! ADD DEC PT
  REM END IF
  CIRD$=C$
  REM CURSOR (T3X@17)+7,35 ! POSITION CURSOR
  CURSOR (DLINEX@17)+7,35
  DISPLAY C$;
35  IF VAL(C$) < 12 THEN ! IF VALUE BELOW LIMIT
    ALARM ON
    SET TIMER 1 FOR 1 SECONDS
    WAIT FOR TIMER 1
    ALARM OFF
    DISPLAY
    DISPLAY "ERROR IN CIRCUMFERENCE READING"
    DISPLAY "C$ = ";C$;" C = ";C;" C$ = ";C$
40  IF ERRSTOP$="T" ! IF STOPPING ON DETECTED ERRORS
    SUSPEND
  END IF
  END IF
  T3X=T3X+1 ! INCR LOOP CTR
  APPEND CIRD$ TO "CD.DAT" ! STORE CIRCUMFERENCE DATA
45  CLOSE "CD.DAT"
  TST3$ = TST3$-1 ! DEC # OF TEST CTR
  END IF
  CIRUNLD ! REMOVE SAMPLE FROM LASERMIKE
END PROCEDURE

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A4)

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PROCEDURE CIRLOAD

! THIS PROCEDURE LOADS THE CIGARETTE INTO THE LASER GAGE. IF THE SAMPLE IS
 ! <= 85 MM LONG, IT IS INSERTED INTO THE INSTRUMENT SO THAT THE LASER BEAM
 ! IS 38 MM FROM THE TOBACCO END OF THE CIGARETTE. IF > 85 MM, THE SAMPLE
 ! IS PLACED INTO THE INSTRUMENT AND ADJUSTED TO THE PROPER LENGTH.

10

REM CIGLENX=120 ! ****

REM SPEED 6

SPEED 9

C4

IF CIGLENX < 85 THEN ! IF < 85, DO NOT INSERT AS FAR

15

CONTINUOUS

C3

C2

C7

END CONTINUOUS

ELSE ! IF >=85, INSERT ALL THE WAY

CONTINUOUS

20

C3

C2

C7

C1

END CONTINUOUS

END IF

OPEN ! OPEN FINGERS

25

IF CIGLENX > 85 THEN

C6

CLOSE

CONTINUOUS

C3 ! IF CIG LEN OVER 80 (mm) PUSH CIG IN GAUGE

C2

END CONTINUOUS

30

C3

END IF

END PROCEDURE

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A42

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PROCEDURE CIRCHK
  REM THIS PROCEDURE CHECKS THE LASERMIKE TO SEE IF A SAMPLE IS IN IT. IF A
  REM SAMPLE IS IN THE BEAM, THE SEGMENT ERROR IS TURNED OFF. IF IT IS NOT IN
  REM THE BEAM, THE SEGMENT ERROR IS TURNED ON. THE STATUS OF THE SEGMENT
  REM ERROR IS CHECKED BY READING THE PARAMETERS MESSAGE, WHICH INCLUDES THE
  REM STATUS OF THE SEGMENT ERROR INDICATOR ON THE FRONT PANEL OF THE
  REM LASERMIKE. 3/6/90 WBA
  REM
  DEFINE C$ AS CIRC
  C1$="128"
  WHILE VAL(C1$)>127 ! WAIT FOR SEG ERROR TO BE CLEARED
  REM CERRX=0 ! SET FLAG FOR NO CIRC ERROR
  C$="209" ! MESSAGE TO SEND PARAMETERS, INCLUDING LIGHT BAR STATUS
  SEND C$ ! SEND CODE TO TX C16 RTD DATA
  RECEIVE C$
  C1$=LEN(C$) ! GET LENGTH
  IF C1$>3 THEN ! CORRECT RESPONSE WAS RECEIVED
    C1$=RIGHT$(C$,15) ! GET LIGHT BAR STATUS FROM MESSAGE
    C1$=LEFT$(C1$,7) ! GET MESSAGE CONTAINING SEG ERROR STATUS
  REM DISPLAY C1$
    IF VAL(C1$)>127 THEN ! SEG ERROR=128
      SIHX=0 ! SET FLAG FOR CIR ERROR
      DISPLAY
      DISPLAY "CIRCUMFERENCE SAMPLE MISSING"
      DISPLAY "PLACE SAMPLE IN LASERMIKE IF NECESSARY"
      ERRRESP ! INDICATE ERROR AND GET RESPONSE
      IF FAULT$="S" THEN ! IF UNATTENDED MODE, SKIP
        C1$="127" ! SET TO EXIT LOOP
        PROB$="CIRCUMFERENCE SAMPLE MISSING" ! TROUBLE MESSAGE TO LOG
        LOGPROB ! LOG PROBLEM IN TROUBLE FILE
      END IF
    ELSE
      SIHX=1 ! SET FLAG FOR SAMPLE IN HAND
    END IF
  END IF
  END WHILE
  REM SET TIMER 1 FOR 2 SECOND
  REM WAIT FOR TIMER 1
  END PROCEDURE

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PROCEDURE CIRUNLD
CLOSE
CONTINUOUS
C2
C3
C4
C5
END CONTINUOUS
END PROCEDURE

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PROCEDURE FCO

! THIS PROCEDURE REPOSITIONS THE CIGARETTE IN THE RIGHT HAND, THEN PLACES IT
! IT IN THE FILTER CUTOFF DEVICE AND CUTS OFF THE FILTER TO THE CORRECT
! LENGTH

10

REM PRINT "REPOSITION OF CIG FOR CUTOFF ";TIMES ! *****
CIGREPOS ! REPOSITION THE CIGARETTE AND PICK UP BY FILTER
REM PRINT " REPOSITION COMPLETED; MOVE TO CUTOFF ";TIMES ! *****
REM SPEED 1
REM SPEED 4
REM SPEED 8

15

SPEED 9
CONTINUOUS
FC05
FC04
FC03
FC02

20

END CONTINUOUS
REM ADJX=35-FILLENX ! FIND DOWN DISTANCE
ADJX=35-FILLENX
IF ADJX<17 THEN
DOWN ADJX ! MOVE DOWN TO RIGHT DISTANCE TO CUT FILTER
END IF
AC1_ON ! CUT FILTER OFF
FC03
AC1_OFF

25

REM SW12_ON
REM SPEED 5
FC07 ! MOVE NEAR JET
ADJX=46-FILLENX
IF ADJX<28 THEN
DOWN ADJX ! MOVE TO JET
END IF
SW12_ON

30

REM SET TIMER 1 FOR SECOND
REM
FC07
SW12_OFF
EL3

35

REM SW12_OFF
END PROCEDURE

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PROCEDURE CIGREPOS
REM SPEED 9
SPEED 9
REM SPEED 5
CIGREP3
OPEN
CONTINUOUS
CIGREP2
CIGREP1
END CONTINUOUS
CLOSE
CONTINUOUS
CIGREP4
CIGREP5
FC06
END CONTINUOUS
END PROCEDURE
    
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PROCEDURE FLEN
! THIS IS THE FILTER LENGTH PROCEDURE. ON THE FIRST TIME THROUGH, IT LOWERS
! THE SPINDLE TO SEE THAT THE GAUGE HAS BEEN ZEROED. IT THEN RAISES THE
! SPINDLE AND CHECKS TO SEE THAT IT RAISED. IT ALSO CHECKS WHEN THE SPINDLE
! IS LOWERED TO SEE IF THE GAUGE READS BELOW A CERTAIN VALUE. IF SO, IT
10 ! DOES NOT CLOSE THE HAND, ASSUMING THAT THE SAMPLE WAS DROPPED. IN ALL
! CASES, IF ANY OF THESE TESTS FAIL, THE OPERATOR IS NOTIFIED IF IN THE
! ATTENDED MODE, AND A PROBLEM IS LOGGED INTO THE TROUBLE FILE, IF IN THE
! UNATTENDED MODE. IT ALSO CHECKS FOR AN ERROR MESSAGE FROM THE GAUGE
! INTERFACE. 5/23/90 WBA
DEFINE F$ AS FLGAUGE
IF FLZRO = 0 THEN ! CHK GAUGE ZERO FIRST TIME THRU LOOP
15 REM PRINT "CHECKING FLEN ZERO ";TIME$ ! *****
REPEAT$="T"
WHILE REPEAT$="T" ! REPEAT UNTIL ERROR DOES NOT EXIST
AC2_OFF
SET TIMER 1 FOR 2 SECONDS
WAIT FOR TIMER 1
SW1_ON ! TOGGLE SEND DATA SWITCH
20 SW1_OFF
RECEIVE F$ ! RECEIVE DATA FROM GAUGE
IF (VAL(F$)>.01) OR (VAL(F$)<-.01) THEN
ALARM_ON
SET TIMER 1 FOR 1 SECOND
WAIT FOR TIMER 1
ALARM_OFF
25 DISPLAY
REM DISPLAY F$
DISPLAY " MAKE SURE FOOT IS DOWN AND RESET LENGTH GAUGE "
IF ERRSTOP$="T" THEN ! IF STOPPING ON DETECTED ERRORS
INPUT " ENTER RETURN AFTER RESETTING GAUGE ",Z
FLZRO=1
ELSE
30 PROB$=" FLEN GAUGE NOT ZEROED" ! CREATE TROUBLE MESSAGE
LOGPROB ! LOG IN TROUBLE FILE
REPEAT$="F" ! SET FLAG TO EXIT REPEAT LOOP
END IF
ELSE
FLZRO = 1
REPEAT$="F" ! SET FLAG TO EXIT REPEAT LOOP
35 END IF
END WHILE
END IF
F$="" ! PUT NUL CHAR IN F$
FAULT$="" ! RESET FAULT RECOVERY STRING
REPEAT$="T"
WHILE REPEAT$="T" ! REPEAT UNTIL ERROR DOES NOT EXIST
40 AC2_ON ! RAISE FOOT ON GAUGE
SPEED 9
SET TIMER 1 FOR 1 SECOND
WAIT FOR TIMER 1
READFLEN
IF VAL(F$)<25 THEN ! IF GAUGE FOOT NOT UP
AC2_ON ! ATTEMPT TO RAISE FOOT AGAIN
45 SET TIMER 1 FOR 1 SECOND
WAIT FOR TIMER 1
READFLEN
IF VAL(F$)<25 THEN ! CHECK FOR FOOT NOT TO BE UP
ALARM_ON
SET TIMER 1 FOR 1 SECOND
50 WAIT FOR TIMER 1
ALARM_OFF
DISPLAY
REM DISPLAY F$
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IF ERRSTOP$="T" THEN ! IF STOPPING ON DETECTED ERRORS

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      INPUT " CORRECT PROBLEM AND ENTER (CR) TO CONTINUE ";Z
    ELSE
      PROB$="FL1 FOOT DID NOT GO UP" ! SET DOUBLE STRING
      LOGPROB ! STORE IN TROUBLE FILE
      FAULT$="S" ! SET FLAG TO SKIP THIS FILTER
      REPEAT$="F" ! SET FLAG TO EXIT REPEAT LOOP
    END IF
    DISPLAY
  ELSE
    REPEAT$="F"
  END IF
  ELSE
    REPEAT$="F"
  END IF
END WHILE
REPEAT$="T"
WHILE REPEAT$="T"
  IF ASC(F$)=69 THEN ! IF 'E' ERROR
    ALARM_ON
    SET TIMER 1 FOR 1 SECOND
    WAIT FOR TIMER 1
    ALARM_OFF
    DISPLAY
    DISPLAY " ERROR HAS OCCURED ON BH 100 INTERFACE: POWER DOWN ";
    DISPLAY "AND BACK ON "
    IF ERRSTOP$="T" THEN ! IF STOPPING ON DETECTED ERRORS
      INPUT " THEN ENTER ( CR ) TO CONTINUE ";Z
    ELSE
      PROB$="BH100 INTERFACE ERROR" ! SET TROUBLE MESSAGE
      LOGPROB ! SAVE MESSAGE IN TROUBLE FILE
      FAULT$="S" ! SET FLAG TO SKIP THIS FILTER
      REPEAT$="F" ! SET FLAG TO EXIT REPEAT LOOP
    END IF
  ELSE ! IF NOT INTERFACE ERROR
    REPEAT$="F" ! SET FLAG TO EXIT REPEAT LOOP
  END IF
END WHILE
IF FAULT$()="S" THEN ! IF NO FAULT DETECTED
  CONTINUOUS
  FL2
  FL1
END CONTINUOUS
AC2_OFF ! LOWER FOOT
SET TIMER 1 FOR 1 SECOND
WAIT FOR TIMER 1 ! WAIT FOR FOOT TO DROP
OPEN
SET TIMER 1 FOR 1 SECOND
WAIT FOR TIMER 1 ! WAIT FOR READING TO SETTLE
READFLEN
REM CURSOR (TSX*017)+7,45
CURSOR (DLINEX*017)+7,45
DISPLAY F$
IF VAL(F$) > 10 THEN ! IF SAMPLE IN HAND
  TST5X=TST5X-1 ! DECR SAMPLE CTR
  TSX=TSX+1 ! INCR LOOP CTR
  APPEND FLD$ TO "FL.DAT" ! SAVE FILT LEN DATA
  CLOSE "FL.DAT"
  CLOSE ! CLOSE ONLY IF SAMPLE IN HAND
ELSE
  PROB$="FLEN SAMPLE NOT PRESENT" ! SET TROUBLE MESSAGE
  LOGPROB ! SAVE MESSAGE IN FILE
  SIH$=0 ! SET FLAG FOR NO SAMPLE IN HAND
END IF
AC2_ON
SET TIMER 1 FOR 1 SECOND

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WAIT FOR TIMER 1 ! WAIT FOR FOOT TO RAISE
 REM WIPE PLATFORM WITH HAND IF SAMPLE DROPPED, TO REMOVE SAMPLE
 CONTINUOUS
 FL2
 FL4
 END CONTINUOUS
 END IF ! NO FAULT DETECTED
 END PROCEDURE

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PROCEDURE READFLEN

REM THIS PROCEDURE READS THE FILTER LENGTH GAUGE DATA. IT TOGGLES THE
 REM GAUGE INTERFACE TO SEND THE DATA, THEN WAITS TO RECEIVE THE DATA FROM
 REM THE GAUGE.

10

REM

FINE F\$ AS FLGAUGE

SW1_ON

SW1_OFF ! TOGGLE SEND DATA SWITCH

RECEIVE F\$! RECEIVE LENGTH DATA

REM

DISPLAY F\$

LENFX=LEN(F\$)-1

15

IF LENFX>0 THEN

F\$=LEFT\$(F\$,LENFX) ! GET RID OF UNWANTED CHARS

END IF

IF VAL(F\$)=0 THEN ! **** REMOVE AFTER DEBUGGING; LEAVING PLUG IN GAUGE

CURSOR 23,70

DISPLAY F\$;

END IF

20

REM F=VAL(F\$)+.05 ! ROUND VALUE

REM F\$=STR\$(F) ! CONVERT BACK

REM DECPT\$="."

REM DECLOC\$=INSTR(F\$,DECPT\$) ! FIND THE DEC PT

REM LENFX=VAL(DECLOC\$) ! CONVERT LOC OF DEC PT

REM F\$=MID\$(F\$,1,LENFX+1) ! GET VALUE TO NEAREST TENTH OF MM

FLD\$=F\$

25

REM CURSOR (75*17)+7,45

REM DISPLAY F\$;

REM SET TIMER 1 FOR 3 SECOND

REM WAIT FOR TIMER 1 ! WAIT FOR FOOT TO RAISE

END PROCEDURE

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PROCEDURE FRTDCHK
! THIS PROCEDURE IS TO CHECK THE FILTER RTD INSTRUMENT BEFORE ATTEMPTING TO
! INSERT A SAMPLE INTO IT. IT READS THE METER AND TRYS TO BLOW THE OBJECT
! OUT IF IT FEELS THAT SOMETHING IS ALREADY IN THE INSTRUMENT. IT DOES THIS
! 3 TIMES AND SIGNALS THE OPERATOR IF THERE IS STILL SOMETHING IN THE
10 ! INSTRUMENT, IF IN ATTENDED MODE. IF UNATTENDED, IT LOGS A MESSAGE INTO
! THE TROUBLE FILE FOR TRANSMISSION TO THE WORKSTATION. 4/25/90 WSA
REM PRINT " CHECK IF FRTD INSTR EMPTY ";TIME$ ! *****
SW4_ON ! ACTIVATE INSTRUMENT
SET TIMER 1 FOR 1 SECONDS
WAIT FOR TIMER 1
READFRTD ! READ FILTER RTD DATA
15 REM SW4_OFF
IF (VAL(FR$)>5) THEN ! IF INSTRUMENT NOT EMPTY
REM SW5_ON ! ATTEMPT TO BLOW OBJECT OUT OF INSTRUMENT
SET TIMER 1 FOR 1 SECONDS
REM WAIT FOR TIMER 1
REM SW5_OFF
REM FRTDUNLD ! ATTEMPT TO REMOVE OBJECT FROM INSTRUMENT
20 TRYCTR=0 ! INITIALIZE ATTEMPT COUNTER
FAULT$=""
REPEAT$="T"
WHILE REPEAT$="T"
FRTDUNLD ! ATTEMPT TO BLOW OBJECT OUT OF INSTRUMENT
SW4_ON
READFRTD ! READ METER AGAIN
25 SW4_OFF
IF (VAL(FR$)>5) THEN ! IF INSTRUMENT STILL NOT EMPTY
TRYCTR=TRYCTR+1 ! INCREMENT ATTEMPT COUNTER
IF TRYCTR=3 THEN ! IF THIRD ATTEMPT
DISPLAY
DISPLAY "THERE APPEARS TO BE SOMETHING ALREADY IN THE FILTER RTD ";
30 DISPLAY "INSTRUMENT."
DISPLAY "PLEASE CHECK IT."
ERRRESP ! GET OPERATOR'S INSTRUCTION
IF ERRSTOP$="F" THEN ! IF NOT STOPPING ON DETECTED ERRORS
PROB$="FRTD NOT EMPTY" ! SET TROUBLE STRING
LOGPROB ! LOG PROBLEM IN FILE
REPEAT$="F" ! SET FLAG TO EXIT LOOP
END IF
END IF
35 ELSE ! IF INSTRUMENT NOT EMPTY
REPEAT$="F" ! SET TO EXIT LOOP
END IF
END WHILE
END IF
REM ELSE ! IF INSTRUMENT EMPTY
SW4_OFF ! RELEASE VACUUM
40 REM END IF
REM PRINT " FRTD INSTR CHECK COMPL ";TIME$ ! *****
END PROCEDURE

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PROCEDURE FRTD
  FRTDLOAD ! PUT FILTER ON INSTRUMENT
  READFRTD ! GET FIL RTD DATA
  REM PRINT " FRTD DATA RCVD; DISPLAY AND SAVE ";TIMES ! *****
10  REM CURSOR (T6%*17)+7,56
    CURSOR (DLINEX*17)+7,56
    DISPLAY FR$;
    APPEND FR$ TO "FRTD.DAT" ! SAVE FILT RTD DATA
    CLOSE "FRTD.DAT"
    T6%=T6%+1 ! INCR LOOP CTR
    FRTDUNLD ! REMOVE SAMPLE
15  TST6%=TST6%-1 ! DEC LOOP CNTR FOR TEST
    REM PRINT " FRTD SAMPLE REMOVAL COMPL ";TIMES ! *****
    END PROCEDURE

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PROCEDURE FRTDLOAD
REM SPEED 7
  SPEED 9
  FRTD3
10  CONTINUOUS
  FRTD4
  REM FRTD3
  FRTD2
  FRTD1
  END CONTINUOUS
  SW4_ON
15  SET TIMER 1 FOR 1 SECONDS
  WAIT FOR TIMER 1 ! WAIT FOR VAC TO HOLD FILTER
  OPEN
  SW4_OFF ! LET FILTER GO IN AGAINST PLUG
  REM FRTD2
  REM CLOSE
  FRTD1
20  FRTD6 ! ****
  FRTD4 ! *****
  REM CLOSE
  REM SET TIMER 1 FOR 1 SECOND
  REM WAIT FOR TIMER 1
  SW4_ON
  FRTD5
25  END PROCEDURE

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PROCEDURE READFRD

! THIS PROCEDURE ACTIVATES THE FILTER RTD INSTRUMENT AND READS THE METER.
 ! IT SENDS THE 'XS' MESSAGE TO SEND DATA. THE PROGRAM WAITS IN A LOOP UNTIL
 ! THE DIFFERENCE BETWEEN 2 CONSECUTIVE READINGS IS LESS THAN 2. IT THEN
 ! SAVES THE LAST READING AS THE DATA, WHICH IS FORMATTED FOR FUTURE USE.

10

DEFINE FR\$ AS FDI ! FRD RECEIVE BUFFER
 DEFINE FRT\$ AS FDI ! FRD TRANSMIT BUFFER
 REM SET TIMER 1 FOR .5 SECONDS
 REM WAIT FOR TIMER 1

15

FRT\$="XS"
 DIFF=20 ! PRESET THE DIFFERENCE IN READINGS
 CRL=0 ! CLEAR LAST READING
 WHILE DIFF > 1 ! WAIT UNTIL DIFF IN READINGS < 1
 SEND FRT\$! SEND CODE TO TX RTD DATA
 RECEIVE FR\$

20

rem DISPLAY FR\$;
 FR\$=MID\$(FR\$,2,6)
 REM DISPLAY FR\$
 F=VAL(FR\$) ! STRIP LEADING ZEROS
 REM IF (F=0) OR (F)0 THEN ! IF POSITIVE
 DIFF=ABS(F-CRL) ! GET ABSOLUTE DIFF BET NEW AND LAST READINGS
 CRL=F ! SAVE LAST READING

25

REM END IF
 END WHILE
 FR\$=STR\$(F) ! CONVERT BACK TO STRING

30

rem DISPLAY FR\$
 rem SET TIMER 1 FOR 2 SECOND
 rem WAIT FOR TIMER 1
 END PROCEDURE

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PROCEDURE FRTDUNLD
 SW4_OFF ! RELEASE FIL
 SW5_ON ! ACTIVATE EJECTOR TO BLOW FILTER OUT OF TUBE
 SET TIMER 1 FOR .9 SECONDS
 WAIT FOR TIMER 1
 SW5_OFF
 END PROCEDURE

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PROCEDURE DAT
  REM PROCEDURE TO TRANSFER DATA FOR DATABASE USE. THE DATA IS FORMATTED
  REM INTO 1 FILE HAVING NAME XXXXXXXX.DAT, WHERE XXXXXXXX IS THE ACTUAL
  REM BARCODE OF THE SAMPLE. THE DATA IS THEN COPIED TO \LINK\WORK DIRECTORY
  REM FOR ARCHIVING. THE STATUS OF THE NETWORK IS CHECKED, AND IF OPERATIONAL,
  REM THE DATA IS TRANSMITTED TO G: DRIVE FOR RETRIEVAL BY THE WORKSTATION.
  REM IF THE NETWORK IS NOT OPERATIONAL, THE DATA IS SAVED IN \LINK\WORK\TMP
  REM FOR TEMPORARY STORAGE. 1/15/90 WEA
  REM
  WORKDR$="\LINK\WORK\" ! DRIVE FOR ARCHIVING OF DATA
  WSDDR$="G:" ! WORKSTATION DATA DRIVE
  CLEAR
  DISPLAY
  DISPLAY
  DISPLAY "      TRANSFERRING DATA FOR BARCODE "; ECODE$
  REM BCODE$="1123344" ! ***** REMOVE AFTER TEST
  REM RLFLAG=1 ! ****
  REM CRFLAG=1 ! ****
  REM CFLAG=1 ! ****
  REM DFLAG=1 ! ****
  REM FLFLAG=1 ! ****
  REM FRFLAG=1 ! ****
  REM LINK$="UP" ! ****
  BARCODE.DAT$=WORKDR$+BCODE$+".DAT"
  D$="BC "+BCODE$
  WRITE D$ TO BARCODE.DAT$ ! SAVE BARCODE IN DATA FILE
  D$="DATE "+DATE$ ! GET DATE AND STORE IN FILE
  WRITE D$ TO BARCODE.DAT$
  T$="TIME "+TIME$ ! GET TIME AND STORE IN FILE
  WRITE T$ TO BARCODE.DAT$
  IF RLFLAG=1 THEN ! IF RODLENGTH TESTED
    FOR IX = 1 TO 200
      READ DATA$ FROM "CL.DAT"
      WRITE DATA$ TO BARCODE.DAT$
      IF EOF("CL.DAT") = 1 THEN
        IX=200
      END IF
    NEXT IX
    CLOSE "CL.DAT"
  END IF
  IF CRFLAG = 1 THEN ! IF CIGARETTE RTD TESTED
    FOR IX = 1 TO 200
      READ DATA$ FROM "CRTD.DAT"
      WRITE DATA$ TO BARCODE.DAT$
      IF EOF("CRTD.DAT") = 1 THEN
        IX=200
      END IF
    NEXT IX
    CLOSE "CRTD.DAT"
  END IF
  IF CFLAG = 1 THEN ! IF CIRCUMFERENCE TESTED
    FOR IX = 1 TO 200
      READ DATA$ FROM "CD.DAT"
      WRITE DATA$ TO BARCODE.DAT$
      IF EOF("CD.DAT") = 1 THEN
        IX=200
      END IF
    NEXT IX
    CLOSE "CD.DAT"
  END IF
  IF DFLAG = 1 THEN ! IF DILUTION TESTED
    FOR IX = 1 TO 200
      READ DATA$ FROM "DIL.DAT"
      WRITE DATA$ TO BARCODE.DAT$
      IF EOF("DIL.DAT") = 1 THEN
        IX=200
      END IF
    NEXT IX
    CLOSE "DIL.DAT"
  END IF

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        END IF
        NEXT IX
        CLOSE "DIL.DAT"
    END IF
    IF FLFLAG = 1 THEN ! IF FILTER LENGTH TESTED
10      FOR IX = 1 TO 200
          READ DATA$ FROM "FL.DAT"
          WRITE DATA$ TO BARCODE.DAT$
          IF EOF("FL.DAT") = 1 THEN
              IX=200
          END IF
          NEXT IX
          CLOSE "FL.DAT"
15      END IF
      IF FRFLAG = 1 THEN ! IF FILTER RTD TESTED
          FOR IX = 1 TO 200
              READ DATA$ FROM "FRTD.DAT"
              WRITE DATA$ TO BARCODE.DAT$
              IF EOF("FRTD.DAT") = 1 THEN
20                  IX=200
              END IF
              NEXT IX
              CLOSE "FRTD.DAT"
          END IF
          CLOSE BARCODE.DAT$ ! *****
          CMD1$="COPY "+BARCODE.DAT$ ! INITIALIZE CMD TO TRANSFER DATA
          REM CMD$=CMD1$+" \LINK\WORK" ! CMD TO TRANSFER TO ARCHIVE DIRECTORY
25      REM WRITE CMD$ TO "TRANSFER.BAT" ! SAVE CMD
          IF LINK$()="DOWN" THEN ! IF NETWORK NOT DOWN
              CHECKLNK ! SEE IF NETWORK STILL ACTIVE
          END IF
          IF LINK$="UP" THEN ! IF NETWORK STILL ACTIVE
              CMD$="COMMAND /C COPYDATA "+WORKDR$+" "+BCODE$+".DAT"+", "+WSDDR$
              REM COPY TO SERVER
30          ELSE ! IF NETWORK NOT ACTIVE
              CMD$=CMD1$+" \LINK\WORK\TMP" ! COPY TO TEMPORARY DIRECTORY
          END IF
          WRITE CMD$ TO "TRANSFER.BAT"
          CPYPROB ! PREPARE TO COPY PROBLEM FILE
          CLOSE "TRANSFER.BAT"
          DOS TRANSFER.BAT ! EXECUTE TRANSFER OF DATA
35      REM PRINT
          REM PRINT BARCODE.DAT$ ! PRINT BARCODE OF DATA
          REM PRINT
          REM CMD$="COPY \PERL\ "+BARCODE.DAT$+" LPT1:" ! ***** COPY DATA TO PRINTER
          REM WRITE CMD$ TO "TRANSFER.BAT" ! *****
          REM CLOSE "TRANSFER.BAT"
          REM DOS TRANSFER ! *****
40      IX=0
          DISPLAY "TRANSFER OF DATA COMPLETED."
          DISPLAY
    END PROCEDURE

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: COPYDATA.BAT
: TO COPY DATA FILE FROM TESTSTATION TO WORKSTATION
: IT ATTEMPTS TO COPY FILE, THEN CHECKS TO SEE IF IT EXISTS
: IN G:. IF NOT IT ATTEMPTS TO RECOPY. IF STILL NOT SUCCESSFUL,
: IT COPS THE FILE TO TMP DIRECTORY FOR LATER COPYING. 3/8/93 WBR
10 :
:
: echo off
: copy %1%2 %3
: if exist %3%2 goto finish
: copy %1%2 %3
: if exist %3%2 goto finish
: copy \LINK\WORK\%2 \LINK\WORK\TMP
15 : finish

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PROCEDURE PCHECK
  REM THIS IS THE PAUSE CHECK PROCEDURE.
  REM
  R$=READKEY$ ! SEE IF KEY ENTERED
  IF R$(>)" THEN ! IF KEY ENTERED
    WHILE R$(>)" ! CLEAR KEYBOARD BUFFER
      R1$=R$ ! SAVE LAST KEY INPUT
      DISPLAY R1;
      R$=READKEY$
    END WHILE
    IF R1$="P" THEN ! IF PAUSE KEY ENTERED
      ERRMODE ! ALLOW ERROR MODE TO BE CHANGED, IF NEEDED
    END IF
    DISPLAY
  END IF
END PROCEDURE

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PROCEDURE ABORTRUN

REM THIS PROCEDURE ABORTS TESTING OF SAMPLES. IT ASSUMES THE ROBOT IS CLEAR
 REM OF THE INSTRUMENTS. IT MOVES TO THE NEXT POSITION, BEFORE LEAVING PERL
 REM AND RETURNING TO THE SYSTEM LEVEL. 4/26/98 WBA

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REM
 REM PROB\$="RUN ABORTED" ! SET TROUBLE MESSAGE
 REM LOGPROB ! STORE MESSAGE IN TROUBLE FILE
 NEST1
 SYSTEM
 END PROCEDURE

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PROCEDURE COPYPROB
  REM THIS PROCEDURE COPY 3 THE TROUBLE FILE, IF ONE EXISTS TO THE ARCHIVE
  REM DRIVE AND TO THE WORKSTATION. 3/30/93 WEA
  LOGDR$="\LINK\LOG\" ! ARCHIVE LOG DRIVE
  WSLDR$="H:" ! WORKSTATION LOG DRIVE
  IF PROECTRX() THEN ! IF OPERATIONAL PROBLEM DETECTED
    CMD1$="COPY TROUBLE.DAT "
    TCODE$=SCODE$+".TEL" ! FORM NAME OF TROUBLE FILE
    CMD$=CMD1$+LOGDR$+TCODE$ ! COMMAND TO COPY TO ARCHIVE DRIVE
    WRITE CMD$ TO "TRANSFER.BAT"
    IF LINK$="UP" THEN ! IF NETWORK ACTIVE
      CMD$="COMMAND /C COPYDATA "+LOGDR$+" "+TCODE$+" "+WSLDR$
    ELSE
      CMD$=CMD1$+WORKDR$+"TMP\"+TCODE$ ! COPY TO TMP STORAGE DIRECTORY
    END IF
    WRITE CMD$ TO "TRANSFER.BAT" ! WRITE COMMAND
  END IF
END PROCEDURE

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PROCEDURE CLRHCPR
 ! THIS PROCEDURE CLEAR SAMPLES FROM THE FEED HOPPER AT THE END OF A RUN,
 ! IF SAMPLES HAVE BEEN LEFT OVER. THE LENGTH CAMERA IS USED TO DETECT
 ! THE PRESENCE OF A SAMPLE. THE SAMPLE IS REMOVED AND DROPPED ON THE TABLE.
 ! 2/9/90 WBA

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SPEED 9
 OPEN
 FAULT\$=""
 REM PRINT "FEEDIN SAMPLE ";TIME\$! *****
 GETLEN ! SEE IF SAMPLE ALREADY THERE
 IF VAL(CLEND\$) < 77 THEN ! IF SAMPLE NOT THERE
 FEEDSAMP ! FEED SAMPLE OUT OF HOPPER
 END IF
 GETLEN ! SE IF SAMPLE THERE
 WHILE VAL(CLEND\$) > 77 ! WHILE SAMPLES ARE PRESENT
 HOP4
 HOP3
 HOP1
 CLOSE
 HOP3
 HOP4
 OPEN
 FEEDSAMP ! TRY AGAIN TO FEED SAMPLE
 SET TIMER 1 FOR 2 SECONDS
 WAIT FOR TIMER 1
 GETLEN ! SEE IF SAMPLE THERE
 END WHILE
 REM PRINT " PICKUP COMPLETED ";TIME\$! *****
 END PROCEDURE

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Claims

1. Apparatus (10) for measuring a physical characteristic of a plurality of smoking articles (20), comprising:
 5 means (503) for gripping and releasing a smoking article;
 means (503) for maneuvering a gripped smoking article within a range of motion;
 means for receiving one of the said plurality of smoking articles at a first location within the said range of motion;
 means (200)(600)(700)(800)(850) for measuring a physical characteristic of a smoking article or a component (450) of a smoking article, the measuring means being at a second location within the said
 10 range of motion; and
 means (1000) for controlling the gripping and releasing means and the maneuvering means to grip the smoking article or component at the first location and to maneuver the smoking article or component to the measuring means so that the physical characteristic of the one smoking article can be measured.
- 15 2. Apparatus (10) according to claim 1, in which the controlling means (1000) is a microprocessor which controls the gripping and releasing means (503) to release the smoking article (20) or component (450) at the measuring means (200)(600)(700) (800)(850) so that the physical characteristic can be measured and to grip the smoking article or component at the measuring means following the measurement.
- 20 3. Apparatus (10) according to claim 1 or 2, in which the gripping and releasing means and the maneuvering means comprise a robot (503) having a first (510) and a second (520) member, the first and second members being movable in opposition for gripping therebetween a smoking article (20) or component (450).
- 25 4. Apparatus (10) according to any preceding claim, in which the measuring means (200)(600)(700) comprises first means for measuring a first physical characteristic of a smoking article (20) located at the second location and second means for measuring a second physical characteristic of a smoking article the second measuring means being located at a third location within the said range of motion, and in which the controlling means (1000) controls the gripping and releasing means (503), and the maneuvering means (503) to grip the smoking article at the first location and to maneuver the smoking article to one of the first and second measuring means whereby one of the first and second physical characteristics can be
 30 measured.
- 35 5. Apparatus (10) according to claim 4, in which the controlling means (1000) controls the gripping and releasing means (503) and the maneuvering means (503) to maneuver the smoking article from the said one of the first and second measuring means (200)(600)(700) to the other of the first and second measuring means whereby the other of the first and second physical characteristics can be measured.
- 40 6. Apparatus (10) according to any preceding claim in which the measuring means (200)(600)(700) comprises more than one means for measuring more than one selected physical characteristic of a smoking article in which each said means is located at a different location within the said range of motion, the means being means (600) for measuring circumference, means (700) for measuring ventilation, means (700) for measuring pressure drop or means (200) for measuring length, and in which the controlling means (1000) controls the gripping and releasing means (503) and the maneuvering means (503) to maneuver one smoking article to one or more of the measuring means.
- 45 7. Apparatus (10) according to claim 4, 5 or 6 in which the controlling means (1000) comprises a means for providing a test sequence identifying one or more physical characteristics of the smoking article (20) to be measured, in which the controlling means is responsive to the test sequence and controls the gripping and releasing means (503) and the maneuvering means (503) to maneuver the gripped smoking article or component (450) to one or more of the measuring means (200)(600)(700)(800)(850) so that the one or
 50 more identified physical characteristics can be measured.
8. Apparatus (10) according to claim 7 in which the test sequence identifies the order in which the measurements of each smoking article (20) are to be made.
- 55 9. Apparatus (10) according to claim 7 or 8, in which the test sequence identifies the order in which the measurements of each smoking article (20) in the plurality of smoking articles are to be made.
10. Apparatus (10) according to any preceding claim further comprising:

means (300) for severing a component (450) of the smoking article (20) from the smoking article, the severing means being within the said range of motion;

means (800)(850) for measuring a physical characteristic of a smoking article component, the measuring means being within the said range of motion; and

5 means (1000) for controlling the gripping and releasing means (503) and the maneuvering means (503) to grip the smoking article and maneuver the one smoking article to the severing means, and to maneuver the smoking article component to the measuring means so that the physical characteristic of the smoking article component can be measured.

10 11. Apparatus (10) according to claim 10 in which the measuring means comprises a first measuring means (800) for measuring a first physical characteristic of a smoking article component (450) and a second means (850) for measuring a second physical characteristic of a smoking article component, and in which the controlling means (1000) controls the gripping and releasing means (503) and the maneuvering means (503) to grip and maneuver the smoking article component to one of the first and second measuring means whereby one of the first and second physical characteristics can be measured.

12. Apparatus (10) according to claim 11 in which the controlling means (1000) controls the gripping and releasing means (503) and the maneuvering means (503) to maneuver the smoking article component (450) from the one of the first and second measuring means (800)(850) to the other of the first and second measuring means whereby the other of the first and second physical characteristics of the smoking article component can be measured.

13. Apparatus (10) according to claim 11 or 12, in which the first and second measuring means are means (800) for measuring pressure drop and means (850) for measuring length.

25 14. Apparatus (10) according to any of claims 10 to 13 in which the controlling means (1000) comprises a means for providing a test sequence identifying one or more physical characteristics of the smoking article component (450) to be measured, and in which the controlling means is responsive to the provided test sequence and controls the gripping and releasing means (503) and the maneuvering means (503) to maneuver the gripped smoking article component to measuring means (800)(850) so that the one or both identified physical characteristics of the smoking article component can be measured.

15. Apparatus (10) according to claim 14, in which the test sequence identifies the order in which the measurements of the smoking article component (450) are to be made.

35 16. Apparatus (10) according to claim 14 or 15 in which the test sequence identifies the order in which the measurements of each smoking article component (450) of the plurality of smoking articles (20) are to be made.

40 17. Apparatus (10) according to any of claims 10 to 16, in which the controlling means (1000) controls the gripping and releasing means (503) and the maneuvering means (503) to grip one smoking article (20) to maneuver the smoking article to a measuring means (200)(600)(700) so that a first physical characteristic of the smoking article can be measured, and then to the severing means (300), thereby to sever a component (450) from the smoking article, and to maneuver the smoking article component to another measuring means (800)(850) so that a physical characteristic of the smoking article component can be measured.

45 18. Apparatus (10) according to claim 17, in which the measuring means comprise more than one means (800)(850) for measuring more than one physical characteristic of a smoking article component (450) at more than one location within the said range of motion, and more than one means (200)(600)(700) for measuring more than one physical characteristic of a smoking article (20) at more than one location within the said range of motion, and the controlling means (1000) comprises a means for providing a test sequence identifying one or more physical characteristics of the smoking article (20) and one or more physical characteristics of the smoking article component (450) to be measured, in which the controlling means is responsive to the provided test sequence and controls the gripping and releasing means (503) and the maneuvering means (503) to maneuver the gripped smoking article to one or more of the measuring means for the smoking article, and the severing means (300) and one or more identified physical characteristics of the smoking article and the smoking article component can be measured.

19. Apparatus (10) according to claim 18, in which the test sequence identifies the order in which the meas-

urements of the smoking article (20) and the smoking article component (450) are to be made such that the physical characteristics of the smoking article are obtained prior to the physical characteristics of the smoking article component.

- 5 20. Apparatus (10) according to claim 18 or 19, in which the test sequence identifies the order in which the measurements of each smoking article (20) and smoking article component (450) of the plurality of smoking articles are to be made such that the physical characteristics of each smoking article are obtained prior to the physical characteristics of the smoking article component.
- 10 21. Apparatus (10) according to any of claims 10 to 20 further comprising a further means (900) for receiving a smoking article (20) at a location within the said range of motion in which the controlling means (1000) controls the gripping and releasing means (503) and the maneuvering means (503) to release the smoking article onto the said further receiving means and then to grip the smoking article by its component (450) on the said further receiving means, to maneuver the smoking article to the severing means (300), and to grip the smoking article component during the severing process.
- 15 22. Apparatus (10) according to any of claims 10 to 21, in which the smoking article component is a filter rod (450) of a cigarette (20), the apparatus further comprising means (400) for deshredding the severed filter component of a cigarette, and in which the controlling means (1000) controls the gripping and releasing means (503) and the maneuvering means (503) to maneuver a severed filter to the deshredding means following the severing operation.
- 20 23. A method for measuring a physical characteristic of a plurality of smoking articles in a test station having a means for gripping and releasing a smoking article, means for maneuvering a gripped smoking article within a range of motion, means for receiving one of a plurality of smoking articles at a first location within the range of motion, means for measuring a physical characteristic of a smoking article, the measuring means being at a second location within the range of motion; and microprocessor means for controlling the gripping and releasing means and the maneuvering means, comprising:
 - providing a plurality of smoking articles;
 - 25 feeding one smoking article to the receiving means;
 - 30 gripping the fed smoking article at the receiving means;
 - maneuvering the gripped smoking article to the measuring means; and
 - measuring the physical characteristic of the smoking article.
- 35 24. A method according to claim 23 further comprising releasing the smoking article at the measuring means so that the physical characteristic can be measured and gripping the smoking article at the first measuring means following the measurement.
- 40 25. A method according to claim 23 or 24, in which the gripping and releasing means and the maneuvering means further comprise a robot having a first member and a second member being movable in opposition, and gripping and releasing the smoking article further comprises moving the first and second members together for gripping a smoking article and moving the first and second members apart to release the smoking article.
- 45 26. A method according to claims 23, 24 or 25, in which the test station includes more than one means for measuring more than one physical characteristic of a smoking article and in which each means is located at a different location within the said range of motion, the means being means for measuring circumference, means for measuring ventilation and pressure drop or means for measuring length, the method further comprising:
 - providing a test sequence identifying one or more physical characteristics of the smoking article to be measured; and
 - 50 gripping and maneuvering the smoking article to one or more of the measuring means in response to the provided test sequence so that the one or more identified physical characteristics can be measured.
- 55 27. A method according to claim 26, in which providing the test sequence comprises identifying the order in which the measurements of the smoking article are to be made.
28. A method according to claim 26 or 27, in which providing the test sequence further comprises identifying the order in which the measurements of each smoking article in the plurality of smoking articles are to be

made.

- 5 29. A method for measuring a physical characteristic of a component of a plurality of smoking articles in a test station having means for gripping and releasing a smoking article, means for maneuvering a gripped smoking article within a range of motion, means for receiving one of said plurality of smoking articles at a first location within the range of motion, means for severing the component of a smoking article from the smoking article, the severing means being located at a second location within the range of motion, means for measuring a physical characteristic of a smoking article component, the measuring means being at a third location within the range of motion, and microprocessor means for controlling the gripping and releasing means and the maneuvering means, comprising:
- 10 providing a plurality of smoking articles;
feeding one smoking article to the receiving means;
gripping the one fed smoking article by its component;
maneuvering the gripped smoking article to the severing means;
15 severing the smoking article component from the one smoking article;
maneuvering the one smoking article component to the measuring means; and
measuring the physical characteristic of the one smoking article.
- 20 30. A method according to claim 29 further comprising releasing the smoking article component at the measuring means so that the physical characteristic of the one smoking article component can be measured and gripping the smoking article component at the measuring means following the measurement.
- 25 31. A method according to claim 29 or 30, in which the gripping and releasing means and the maneuvering means further comprise a robot having a first member and a second member movable in opposition and wherein gripping the one smoking article or one smoking article component further comprises moving the first and second members together and releasing the one smoking article component further comprises moving the first and second members apart.
- 30 32. A method according to claim 29, 30 or 31, in which the measuring means comprises one or more means for measuring more than one or more physical characteristic of a smoking article component the means being means for measuring pressure drop and means for measuring length, and one or more means for measuring one or more physical characteristics of a smoking article, each measuring means being located at a different location within the said range of motion, the method further comprising:
- 35 providing a test sequence identifying one or more of the physical characteristics of the smoking article and the smoking article component to be measured; and
gripping and releasing and maneuvering the smoking article to one or more of the measuring means and the severing station in response to the identified sequence so that the one or more of the identified physical characteristics of the smoking article and the smoking article component can be measured.
- 40 33. A method according to claim 32, in which providing the test sequence further comprises identifying the order in which the measurements of the smoking article and the smoking article component are to be made.
- 45 34. A method according to claim 32 or 33, in which providing the test sequence further comprises identifying the order in which the measurements of each smoking article and smoking article component of the plurality of smoking articles are to be made.
- 50 35. A method according to claim 32, 33 or 34, in which the test station includes a further means for receiving a smoking article at a location within the said range of motion and in which maneuvering the gripped smoking article to the severing means further comprises:
- maneuvering the gripped article to the said further receiving means;
releasing the smoking article on the said further receiving means;
gripping the smoking article component while the smoking article is on the said further receiving means; and
maneuvering the smoking article to the severing means so that the gripping means grips the smoking article component during the severing process.
- 55 36. A method according to claim 35, in which the smoking article and its component further comprise a cigarette having a tobacco-containing rod and a filter, the method further comprising:
maneuvering the gripped filter severed from the cigarette to a means for deshredding the filter of

any tobacco prior to measuring the physical characteristic of the filter, the deshredding means being at a location within the said range of motion.

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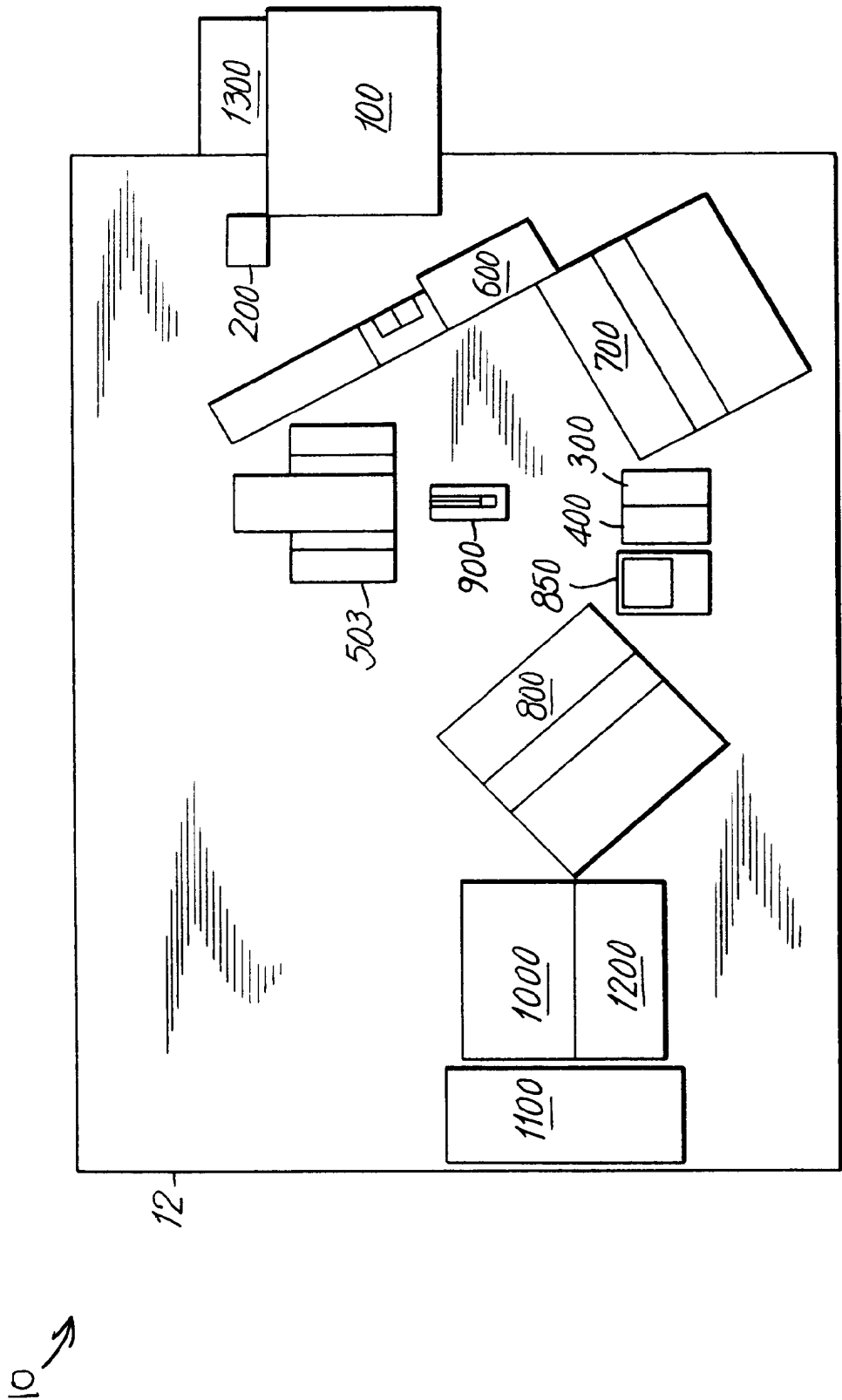
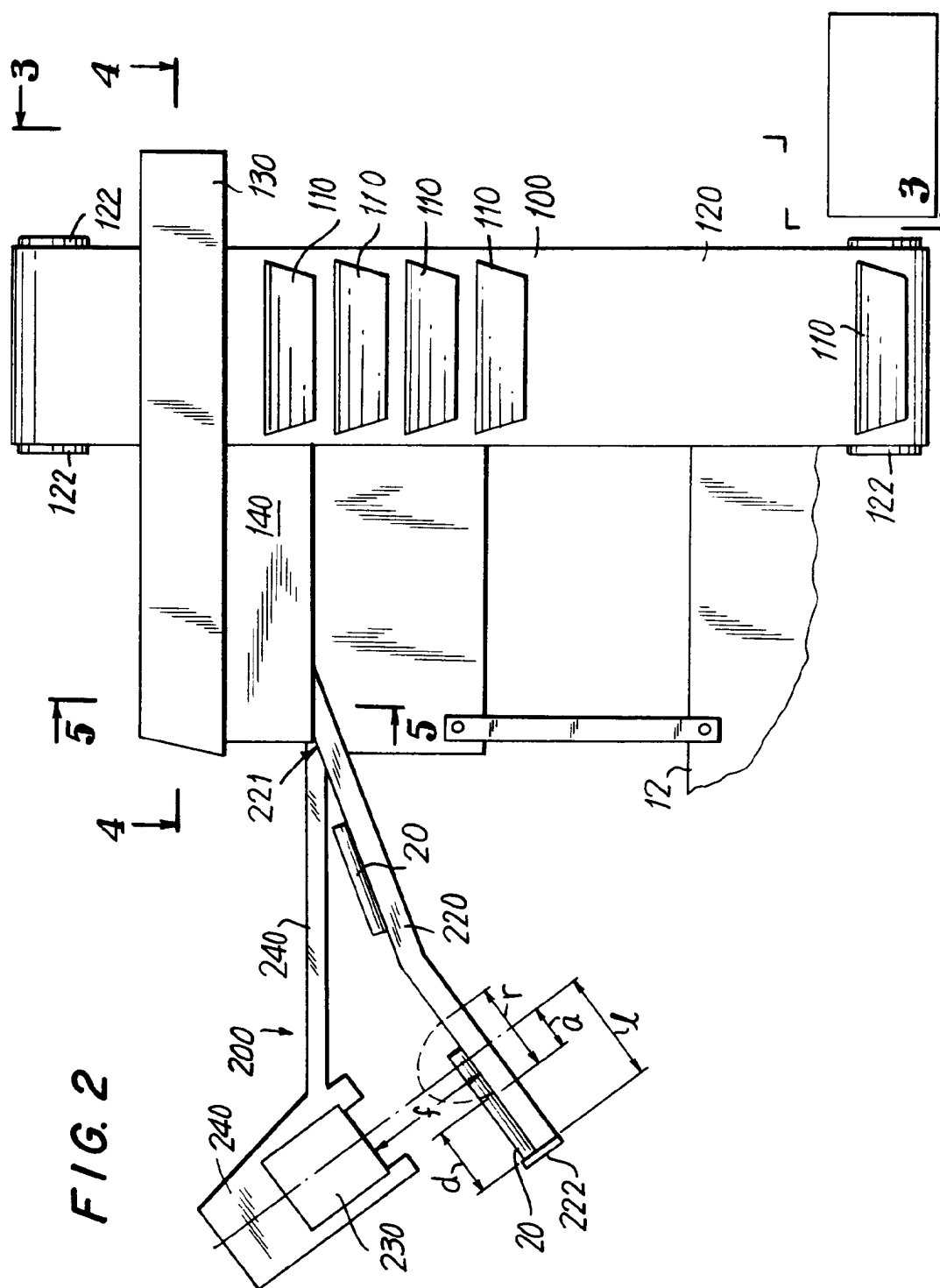
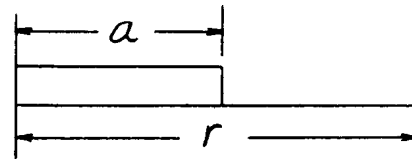
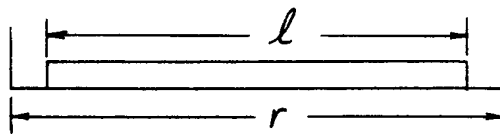
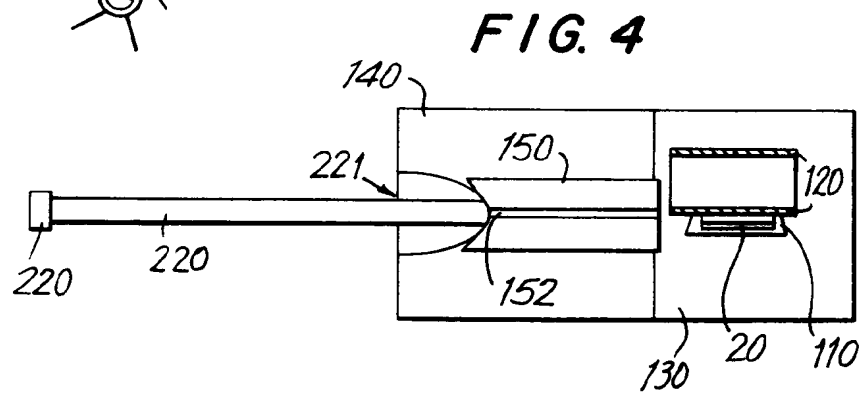
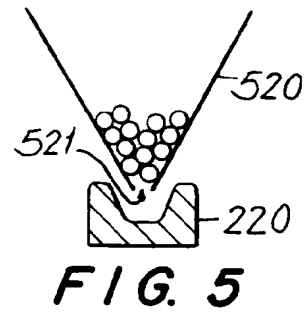
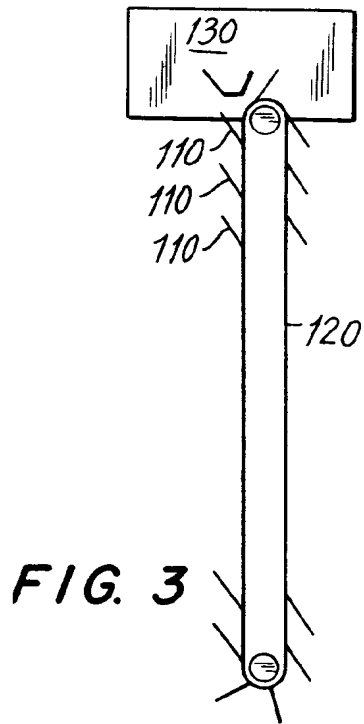
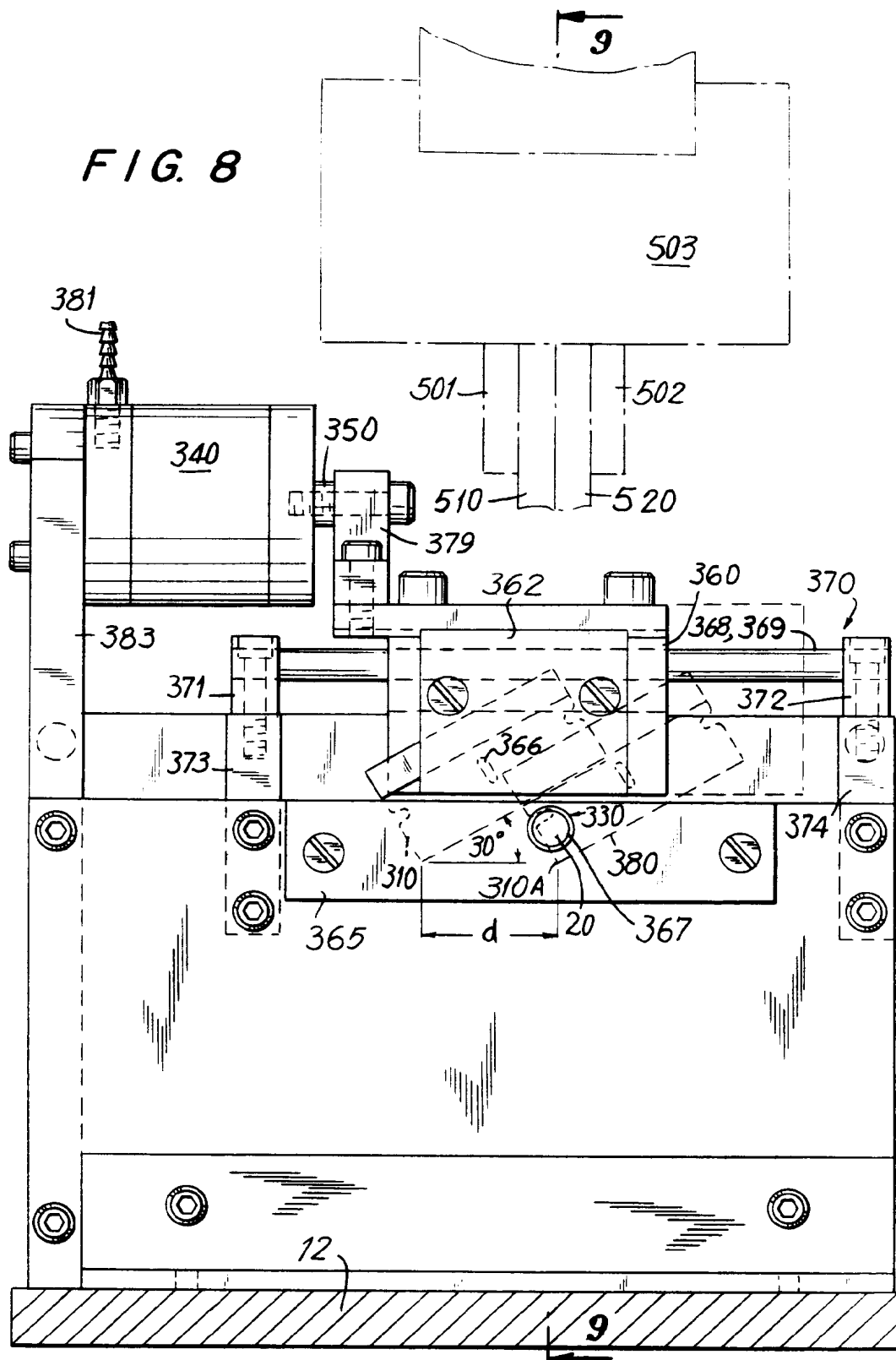
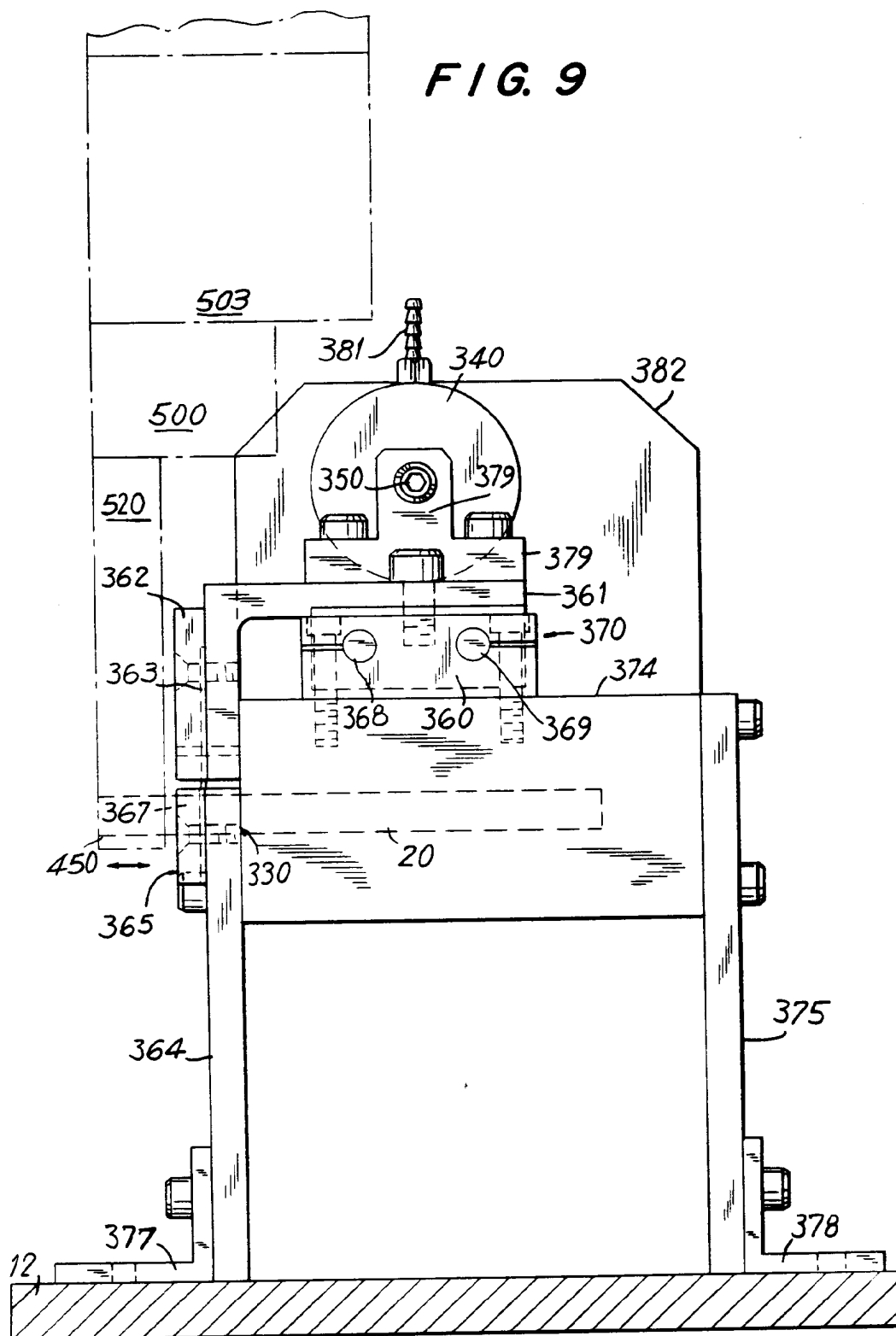


FIG. 1









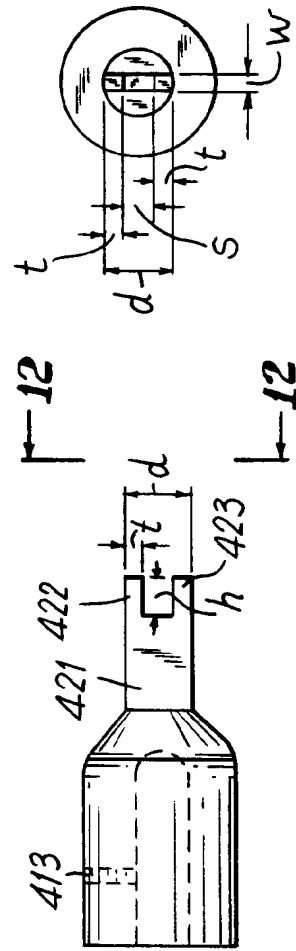
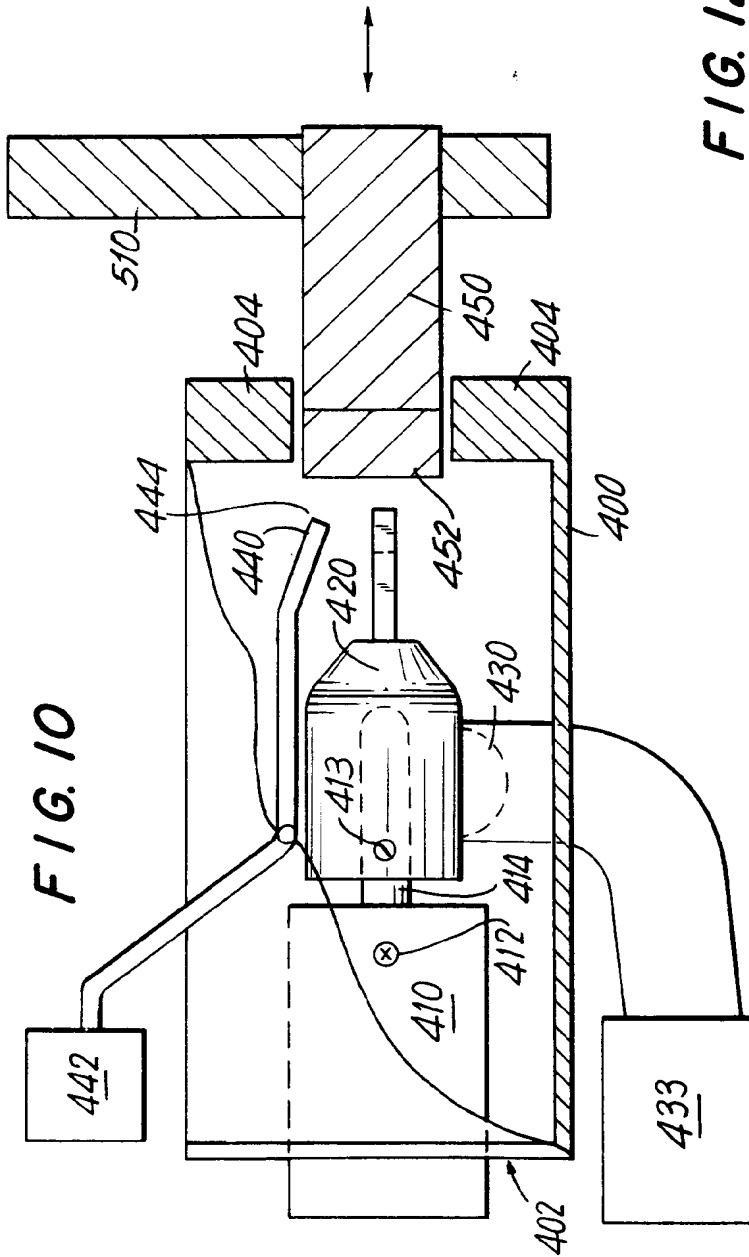
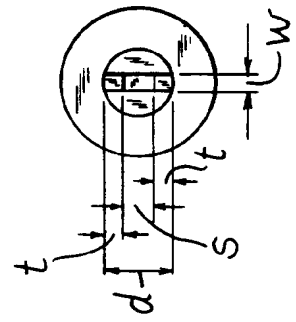
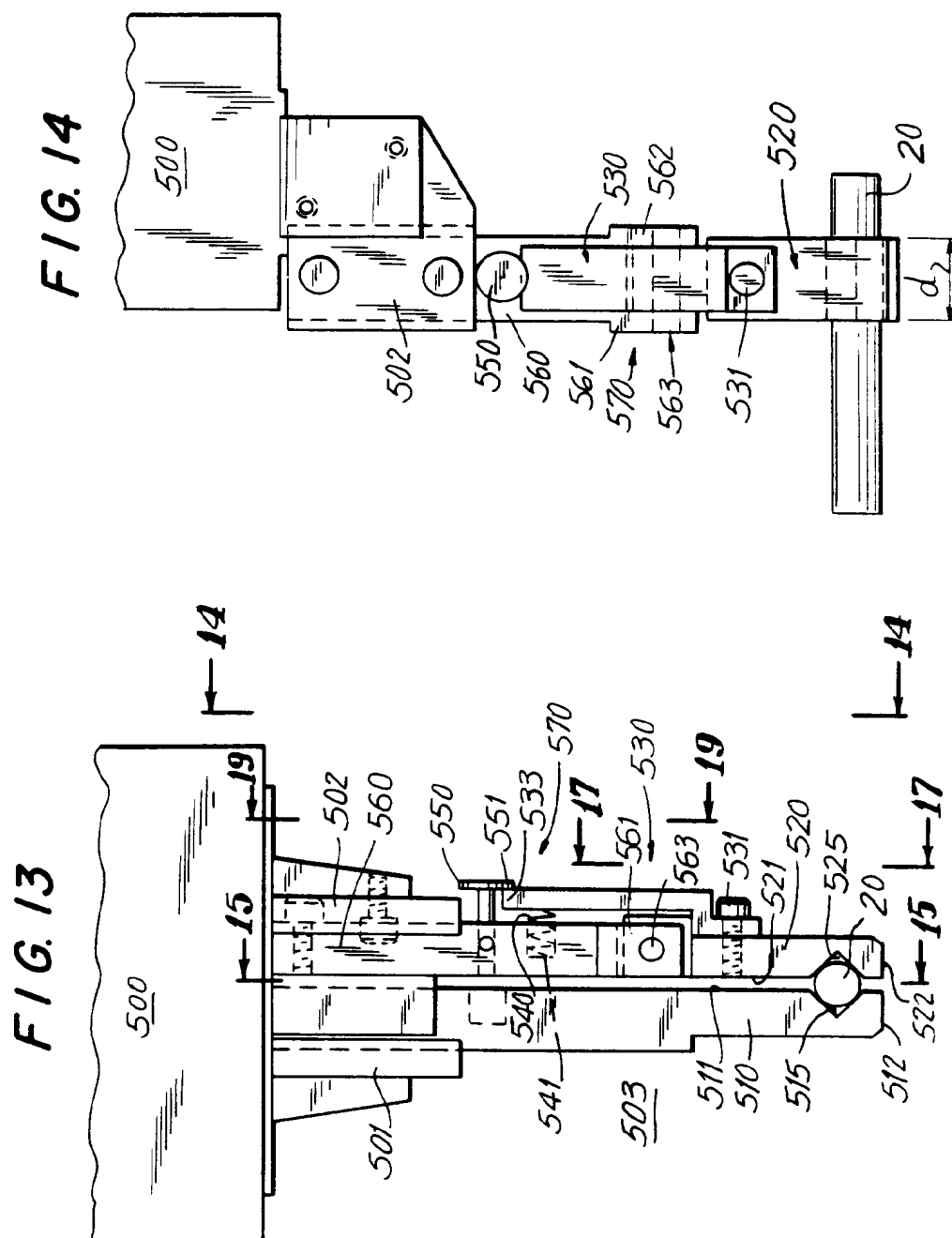
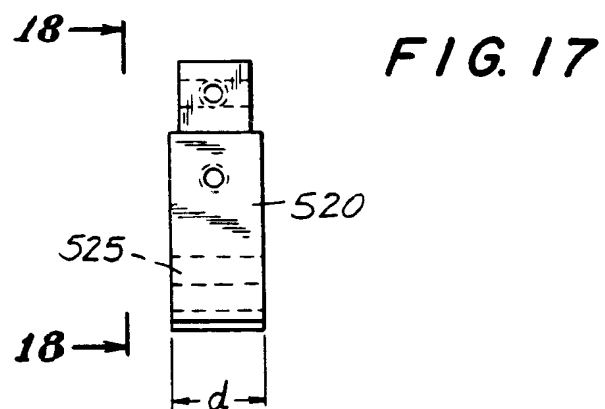
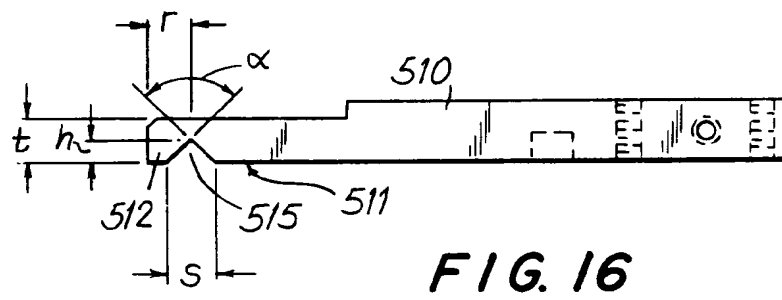
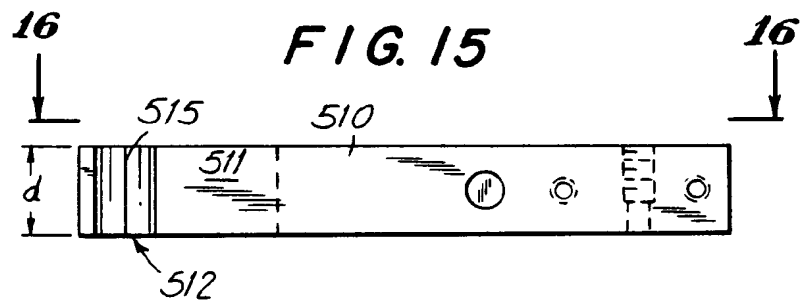


FIG. 12







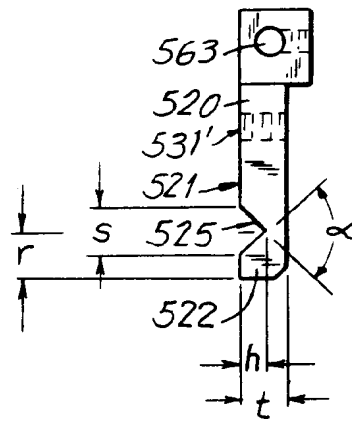
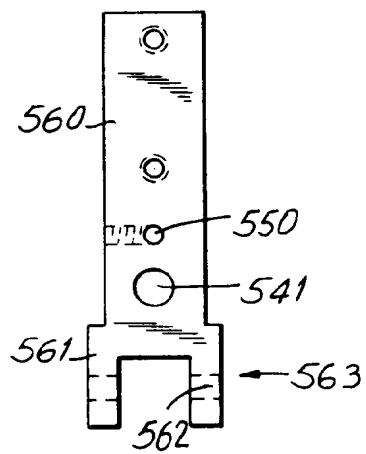


FIG. 18

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FIG. 19

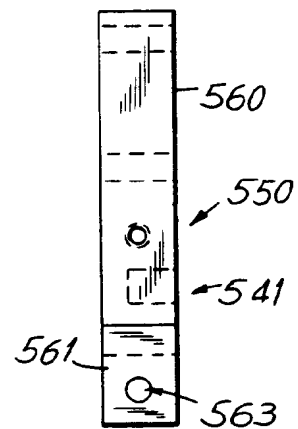


FIG. 20

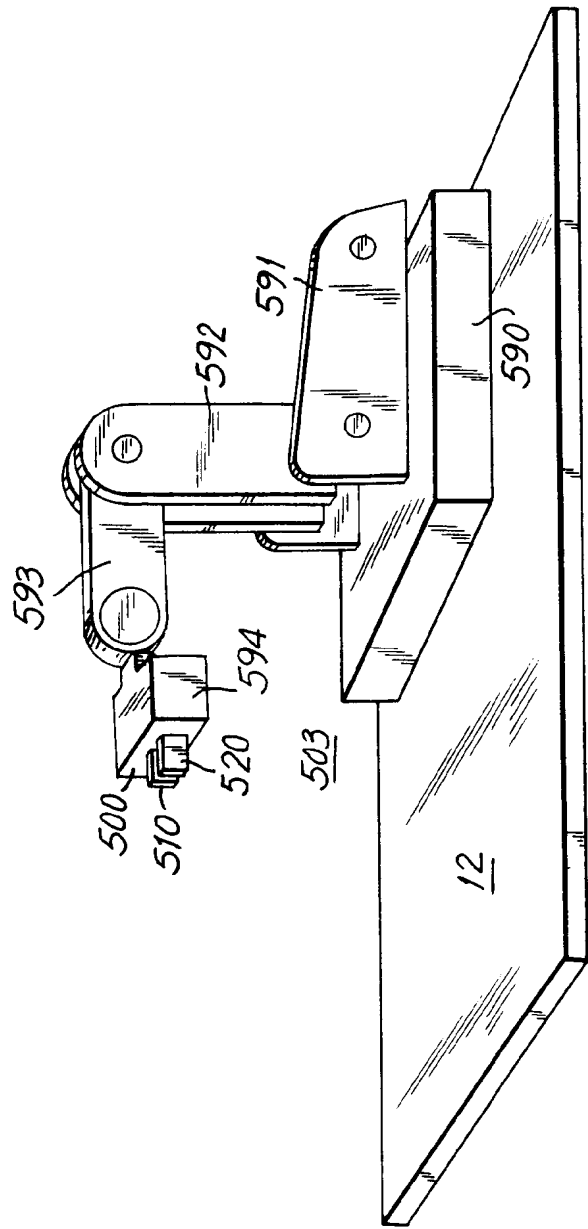


FIG. 21

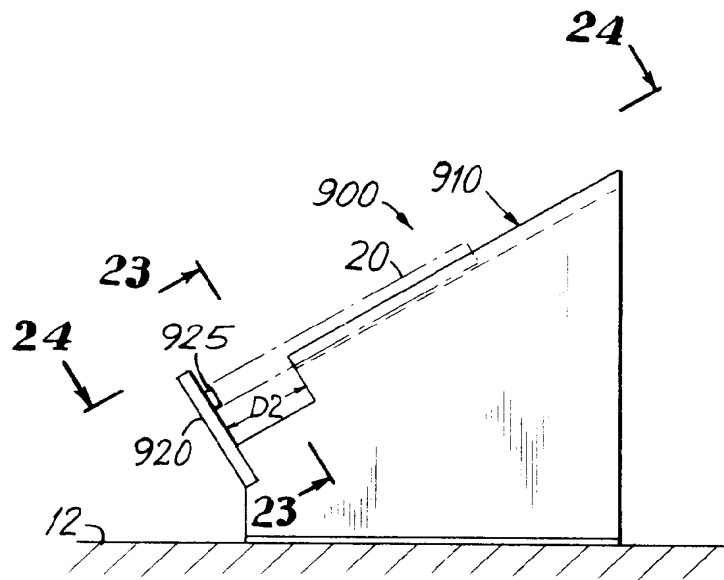


FIG. 22

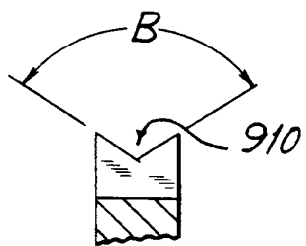


FIG. 23

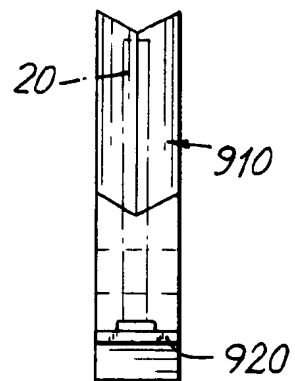


FIG. 24